

<h1 style="text-align: center;">UTILITY PATENT APPLICATION TRANSMITTAL</h1> <p><i>(Only for new nonprovisional applications under 37 CFR 1.53(b))</i></p>	Attorney Docket No. 826.1605/JDH
	First Named Inventor or Application Identifier:  Hiroaki TAKEBE, et al.
	Express Mail Label No.

JD759 U.S. PTO  
 09/577340  
 05/24/00

<b>APPLICATION ELEMENTS</b> <i>See MPEP chapter 600 concerning utility patent application contents.</i>	<b>ADDRESS TO: Assistant Commissioner for Patents</b> <b>Box Patent Application</b> <b>Washington, DC 20231</b>
--	---

1. ☒ Fee Transmittal Form
2. ☒ Specification, Claims & Abstract ..... [ Total Pages: 62 ]
3. ☒ Drawing(s) (35 USC 113) ..... [ Total Sheets: 18 ]
4. ☒ Oath or Declaration ..... [ Total Pages: 4 ]
  - a. ☒ Newly executed (original or copy)
  - b. ☐ Copy from a prior application (37 CFR 1.63(d)) (for continuation/divisional with Box 17 completed)
    - i. ☐ **DELETION OF INVENTOR(S)**  
 Signed statement attached deleting inventor(s) named in the prior application, see 37 CFR 1.63(d)(2) and 1.33(b).
5. ☐ Incorporation by Reference (usable if Box 4b is checked)  
 The entire disclosure of the prior application, from which a copy of the oath or declaration is supplied under Box 4b, is considered as being part of the disclosure of the accompanying application and is hereby incorporated by reference therein.
6. ☐ Microfiche Computer Program (Appendix)
7. ☐ Nucleotide and/or Amino Acid Sequence Submission (if applicable, all necessary)
  - a. ☐ Computer Readable Copy
  - b. ☐ Paper Copy (identical to computer copy)
  - c. ☐ Statement verifying identity of above copies

### ACCOMPANYING APPLICATION PARTS

8. ☒ Assignment Papers (cover sheet & document(s))
9. ☐ 37 CFR 3.73(b) Statement (when there is an assignee)      ☒ Power of Attorney
10. ☐ English Translation Document (if applicable)
11. ☐ Information Disclosure Statement (IDS)/PTO-1449 [ ] Copies of IDS Citations
12. ☒ Preliminary Amendment
13. ☒ Return Receipt Postcard (MPEP 503) (Should be specifically itemized)
14. ☐ Small Entity Statement(s)      [ ] Statement filed in prior application, status still proper and desired.
15. ☒ Certified Copy of Priority Document(s) (if foreign priority is claimed)
16. ☐ Other:

### 17. If a CONTINUING APPLICATION, check appropriate box and supply the requisite information:

[ ] Continuation [ ] Divisional [ ] Continuation-in-part (CIP) of prior application No:        /       

### 18. CORRESPONDENCE ADDRESS

STAAS & HALSEY LLP  
 Attn: James D. Halsey, Jr.  
 700 Eleventh Street, N.W., Suite 500  
 Washington, DC 20001

Telephone: (202) 434-1500  
 Facsimile: (202) 434-1501

APPLICATION FOR  
UNITED STATES LETTERS PATENT  
SPECIFICATION

Inventor(s): Hiroaki TAKEBE, Yoshinobu HOTTA  
and Satoshi NAOI

Title of the Invention: PATTERN SEGMENTATION APPARATUS AND  
PATTERN RECOGNITION APPARATUS

## **PATTERN SEGMENTATION APPARATUS AND PATTERN RECOGNITION APPARATUS**

### **Background of the Invention**

#### **5 Field of the Invention**

The present invention relates to a pattern segmentation apparatus and a pattern recognition apparatus, and more specifically to an application in which a one-character area is to be segmented from a character string image.

10

#### **Description of the Related Art**

In a conventional character recognizing process, it is necessary to segment a pattern corresponding to a character from a character string image. In this segmenting process, there are three main processes, that is, a labeling process, an overlap integrating process, a vertical integrating process (for horizontal writing), or a horizontal integrating process (for vertical writing). However, when two or more characters touch each other, or when two or more characters are written as incorporated into each other, these characters cannot be correctly segmented. Therefore, in the conventional segmenting process, the following method has been adopted to correctly segment

15

20

25

the above described touching characters.

(1) A black pixel projection histogram (vicinal distribution) in the character string direction is generated, and the point of the minimum value is defined as a section point.

(2) The upper and lower outline of a character string is traced, and the point of the minimum value is defined as a section point.

However, some shapes of characters or the touching portions between characters do not indicate the minimum value of the vicinal distribution or the outline of touching points. Therefore, in the conventional method, there has been the problem that characters cannot be correctly sectioned at the touching point.

When the state of an image is not good, and when the image has a number of uneven portions in a pattern, a large number of section points are generated. Therefore, the entire system cannot be free from a bad influence of excess division according to a hypothetical verification.

#### Summary of the Invention

The present invention aims at providing a pattern segmentation apparatus and a pattern recognition

apparatus capable of improving the segmentation precision of a character touching pattern.

To solve the above described problem, the present invention compares the feature amount of a category with the feature amount of an image to segment the portion corresponding to the feature amount of the category from the image.

Thus, it is possible to segment a pattern corresponding to the feature amount of the category at the location of the pattern. Even when the touching position between patterns does not correspond to the minimum point of the black pixel projection histogram, patterns can be segmented at the position between the patterns. In addition, it is possible to collectively segment a portion corresponding to the feature amount of a category from an image. Therefore, although an image has a number of uneven portions in a pattern to be segmented, one pattern can be prevented from being divided into a large number of areas at the minimum point of the pattern, thereby improving the segmentation precision.

According to an aspect of the present invention, the first and the last elements of the feature amount set as an element sequence of a category in the array direction are independently moved in the character

string array direction to allow the feature amount of the category to correspond to the feature amount of the character string image.

Thus, even when there arises the distortion or the deformation in a character string image, the comparison precision can be maintained between the feature amount of a category and the feature amount of the character pattern of the character string image, thereby preventing the feature amount of the category from not being matched when various character string images are input.

According to another aspect of the present invention, the first point of a category corresponding to the element of the character string image in the array direction is entered, and the next segmentation position is obtained from the element of the character string image corresponding to the first point of the category.

Thus, it is possible to extract another character area from a character string image such that other areas corresponding to the category can be serialized in the character string image, thereby efficiently extracting a plurality of character areas from the character string image.

According to a further aspect of the present

invention, when there are a plurality of segmentation areas from an image, the segmentation areas can be combined with each other such that there are no areas, in the image, not corresponding to any category to be recognized.

Thus, it is possible to allow all areas in an image to be segmented to correspond with any category to be recognized. When there is a pattern remaining as not corresponding to any category, the segmentation position can be discarded, and the optimum segmentation position can be obtained even when a plurality of segmentation areas are obtained from an image. For example, an image containing only character strings does not include any pattern other than characters. Therefore, when a pattern not corresponding to any character is segmented from an image containing only character strings, it is determined that the segmentation position is wrong. Therefore, a wrong segmentation position can be avoided by determining a segmentation position such that all segmentation results from a character string to be segmented correspond to any character category, thereby improving the segmentation precision.

In addition, according to a further aspect of the present invention, the feature amount for segmentation

of a category and the feature amount for recognition of a category are separately set, and a pattern segmented using the feature amount for segmentation of a category is recognized using the feature amount for recognition of a category.

Thus, it is possible to check whether or not a pattern segmented as an area corresponding to a category matches the category, thereby improving the character segmentation precision.

In addition, according to a further aspect of the present invention, when a pattern is segmented using the feature amount for segmentation of a category, the category is output as a recognition result of the pattern.

Thus, a recognition result of a pattern can be obtained only by performing a segmenting process from an image, and it is not necessary to perform a pattern recognizing process separately from a character recognizing process, thereby shortening the time required to obtain a pattern recognition result.

#### Brief Description of the Drawings

FIG. 1 is a block diagram of the configuration of the pattern segmentation apparatus according to an embodiment of the present invention;



FIGS. 2A and 2B show the pattern segmenting method according to an embodiment of the present invention;

5 FIG. 3 is a flowchart of the pattern recognizing method according to the first embodiment of the present invention;

FIG. 4 is a flowchart of the pattern recognizing method according to the second embodiment of the present invention;

10 FIG. 5 shows the method of computing the peripheral features of the category according to an embodiment of the present invention;

15 FIG. 6 shows the method of computing the peripheral features of the category according to an embodiment of the present invention;

FIG. 7 shows the method of computing the difference level using the continuous DP according to an embodiment of the present invention;

20 FIG. 8 shows the path through which the current point is reached in the continuous DP according to an embodiment of the present invention;

FIG. 9 is a flowchart of the method of computing the difference level using the continuous DP according to an embodiment of the present invention;

25 FIG. 10 shows the method of searching for the

starting point according to an embodiment of the present invention;

FIG. 11 shows a part of the result of computing the starting point and the difference level according to an embodiment of the present invention;

FIG. 12 shows the method of searching for the path of the segmentation position from the computation result shown in FIG. 11;

FIG. 13 is a flowchart of the method of computing the segmentation position according to an embodiment of the present invention;

FIG. 14 is a flowchart of the process of generating a path according to an embodiment of the present invention;

FIG. 15 is a flowchart of the process of searching for the base point according to an embodiment of the present invention;

FIG. 16 shows an example of generating a path according to an embodiment of the present invention;

FIG. 17 is a block diagram of the configuration realizing the pattern segmenting process and the pattern recognizing process according to an embodiment of the present invention; and

FIG. 18 shows the method of providing a software program, etc. for performing a pattern segmenting

process and a pattern recognizing process according to an embodiment of the present invention.

#### Detailed Description of the Preferred Embodiments

5           The pattern segmentation apparatus and the pattern recognizing method according to an embodiment of the present invention is described below by referring to the attached drawings.

10           FIG. 1 is a block diagram of the configuration of the pattern segmentation apparatus according to an embodiment of the present invention. In FIG. 1, a feature amount extraction unit 1 extracts the feature amount of an image. A feature amount setting unit 2 sets the feature amount of a category. A feature amount comparison unit 3 compares the feature amount of a category with the feature amount of an image for the entire image to be processed. A segmentation unit 4 segment the portion corresponding to the feature amount of the category from the image based on the comparison result by the feature amount comparison unit 3. A feature amount of a category and a feature amount of an image refer to the feature amount or a part of the feature amount from which the original pattern can be reproduced. For example, the  
25           peripheral features up to the n-th peripheral feature

can be used as the feature amount of the category and the feature amount of the image.

Thus, only the pattern corresponding to the feature amount of a category can be collectively segmented from an image. Therefore, it is possible to prevent a pattern other than a character from being segmented or a character from being segmented in a divided state at a number of points, thereby improving the character segmentation precision. In addition, when a portion corresponding to the feature amount of a character exists in an image, the position of a portion corresponding to the character can be specified even when characters touch each other. Although the touching position of characters does not correspond to the minimum point of the black pixel projection histogram, a character can be segmented at the boundary of characters.

The feature amount of a category and the feature amount of an image are set in the character string array direction. The last and the first portions of the array of the feature amount of the category are independently scanned in the array direction, and the position of the optimum correspondence is obtained in the correspondence between the feature of the category and the feature amount of the image obtained in the

scanning. For example, for the correspondence of the last portion of the array of the feature amount of a category, the correspondence of the first portion of the array of the feature amount of the category is obtained such that the optimum correspondence between the feature amount of the category and the feature amount of the image can be obtained.

Thus, a category can be scanned in an input image by enlarging and reducing the category when the portion corresponding to the feature amount of the category is extracted from the input image, thereby extracting the portion corresponding to the feature amount of the category from the input image with high precision even if a handwritten character is contained in the input image.

FIGS. 2A and 2B show the pattern segmenting method according to an embodiment of the present invention. In the embodiments described below, the feature amount of the category 5 is compared with the feature amount of the input image. This holds true with other categories. In FIG. 2A, the feature amount of the category 5 is set in the y axis direction, the feature amount of the leftmost point Lk of the category 5 corresponds to  $y = 0$ , and the feature amount of the rightmost point Rk of the category 5

corresponds to  $y = y_1$ . On the other hand, it is assumed that the touching characters 257 shown in FIG. 2B are input as an image to be segmented. When the touching characters 257 are input, an x axis is set in the character string direction, the feature amount of the leftmost point L1 corresponds to  $x = 0$ , and the feature amount of the rightmost point R1 touching characters 257 correspond to  $x = x_1$ . Then, the rightmost point Rk and the leftmost point Lk of the category 5 are separately searched for in the range of 0 through  $x_1$  of the x axis, and the position of the optimum correspondence is obtained in the correspondence between the feature amount of the category 5 obtained in the scanning operation and the feature amount of the touching characters 257. As a result, assuming that when the rightmost point Rk of the category 5 corresponds to the  $x_R$  of the x axis, and the leftmost point Lk of the category 5 corresponds to the  $x_L$  of the x axis, the optimum correspondence is obtained between the feature amount of the category 5 and the feature amount of the touching characters 257, the coordinates  $x_L$  and  $x_R$  are candidates for the segmentation positions of the touching characters 257. Assuming that the number of pixels in the horizontal direction of the category 5

is  $dy$ , and the number of pixels of the portion corresponding to the category 5 of the touching characters 257 is  $dy'$ , the portion corresponding to the category 5 can be extracted from the touching characters 257 with high precision by separately scanning the rightmost point  $R_k$  and the leftmost point  $L_k$  of the category 5 in the range of 0 through  $x_1$  of the  $x$  axis even when the number  $dy$  of the pixels in the horizontal direction of the category 5 is different from the number  $dy'$  of the pixels of the portion corresponding to the category 5 of the touching characters 257.

The feature amounts can be compared through a nonlinear enlargement/reduction matching method referred to as a continuous DP (dynamic programming). The continuous DP is described in, for example, 'Pattern Information Processing' by Seiichi Nakagawa, Kyouritsu Shuppan, pp.163-166, 1999.

Thus, it is considered that the feature amount of the portion (portion to be segmented as a character of the category) corresponding to the category in an image is similar to the feature amount of the category. That is, a feature amount is defined for an image, and the portion similar to the feature amount of each category is searched for in the entire

input image. First, the feature amount of each category is entered in a dictionary. Then, the feature amount is obtained for the entire input image, and compared with the feature amount of each category.

5 As a result, information is obtained to what extent each category matches the input image, what portion of the input image matches each category, etc. Practically, for each category, the difference level at each coordinate and the correspondence between the  
10 coordinates exceeding the difference level can be obtained. Especially, the difference level obtained when each coordinate is defined as an end point, and the corresponding starting point are obtained. Assuming that the difference level equals the cost  
15 when a portion of an image is segmented from the starting point to the end point, and the portion is the category, the validity of each of the segmenting operations can be compared with each other. The segmentation position and the recognition result can  
20 be confirmed by searching for the combination of the segmenting operations with the highest validity.

FIG. 3 is a flowchart of the pattern recognizing method according to the first embodiment of the present invention. In the first embodiment, when the  
25 segmentation position in an image can be obtained by



comparing the feature amount of a category, the category is defined as the recognition result of the pattern at the segmentation position. In FIG. 3, first, a normalizing process is performed (step S2) on the input image (step S1). In the normalizing process, the image is enlarged or reduced such that the vertical length equals a predetermined value, and then a smoothing process is performed on the resultant image. Then, the feature amount of the input image after the normalizing process is computed (step S3). The feature amount is represented as a sequence of integers (or vectors). The number of the integers is equal to the number of horizontal pixels of the normalized image. Each integer can be any value from 0 through 100.

Using the feature amount of each category entered in the dictionary, a comparing process through the continuous DP is performed on the entire image (step S4). As a result, the difference level of the optimum correspondence about each category and each coordinate, and the coordinate information about the starting point of the optimum correspondence are obtained. Then, based on the information, the section point is computed (step S5). Practically, assume that each optimum correspondence is represented by a path

obtained by connecting the starting point with the end point, and defining the difference level as a weight. In the sequences of paths, the paths requiring the lowest cost are searched for. The sequences of the paths obtained as a result of the search, that is, the sequences of the starting points and the end points of the paths are output as a section point. In this case, the category for providing the paths is a recognition result.

FIG. 4 is a flowchart of the pattern recognizing method according to the second embodiment of the present invention. According to the second embodiment, the feature amount of the category for recognition is stored in the dictionary separately from the feature amount of the category for segmentation. When the segmentation position in an image is obtained by comparing the feature amount of the category for recognition with the feature amount of the category for segmentation, the pattern recognizing process is performed on the segmentation position using the feature amount of the category for recognition. In FIG. 4, the section point is computed by performing the same process as in steps S1 through S5 shown in FIG. 3 (steps S11 through S15). Then, an image is segmented at the section point (step S16),

and the category is determined (step S18) based on the result of recognizing one character in the segmented pattern (step S17). Furthermore, a plurality of combinations of paths are output in order from the lowest cost. Then, one character is recognized as described above, and the optimum recognition result is defined as a recognition result.

In the above described embodiment, the peripheral features up to the n-th peripheral feature both from top and bottom can be used in horizontal writing. A part of the peripheral features up to the n-th peripheral feature can also be used. In the following example, the primary and secondary peripheral features both from top and bottom are used.

FIG. 5 shows the method of computing the peripheral feature of a category according to an embodiment of the present invention. In the example shown in FIG. 5, the category 5 is described, but other category can be similarly processed. In FIG. 5, the lower side of the enclosing rectangle of the category 5 is referred to as a lower Dk. The y axis is set corresponding to the lower Dk, and the z axis is set vertical to the y axis. In addition, each pixel in the horizontal direction forming part of the category 5 is allowed to correspond to the y

coordinate, and each pixel in the vertical direction forming part of the category 5 is allowed to correspond to the z axis. When a scanning line is vertically extended from the coordinate y of the lower Dk, the distance to the first black pixel of the category 5 is defined as z1. Assuming that the height of the enclosing rectangle of the category 5 is dz, the primary peripheral feature from the lower Dk at the coordinate y of the category 5 can be obtained by the following equation.

$$\text{integer of } (z1 / dz \times 100)$$

Similarly, assuming that the distance to the point at which a white pixel is changed into a black pixel is z2, the secondary peripheral feature from the lower Dk at the coordinate y of the category 5 can be obtained by the following equation.

$$\text{integer of } (z2 / dz \times 100)$$

If the upper side of the enclosing rectangle of the category 5 is referred to as the upper limit, the primary and the secondary peripheral features from the upper limit at the coordinate y of the category 5 can be similarly obtained.

When the upper and lower primary and secondary peripheral features at the coordinate y of the category 5 are obtained, a set of these four values

are allowed to correspond to each point on the  $y$  axis. At this time, the leftmost pixel of the category 5 corresponds to  $y = 0$ , and the rightmost pixel of the category 5 corresponds to  $y = y_1$ . Then, for  $y = 0$  through  $y_1$ , the element sequence obtained by arranging the set of the four values of the upper and lower primary and secondary peripheral features in the  $y$  axis can be defined as the peripheral feature of the category 5.

FIG. 6 shows the computation result of the peripheral feature of the category 5 according to an embodiment of the present invention. FIG. 6A shows the primary peripheral feature from the upper  $U_k$ . FIG. 6B shows the secondary peripheral feature from the upper  $U_k$ . FIG. 6C shows the primary peripheral feature from the lower  $D_k$ . FIG. 6D shows the secondary peripheral feature from the lower  $D_k$ .

When the feature amount of a category is obtained using a learning sample, the number of horizontal pixels is predetermined for each category. Next, for each learning sample, the feature amount is computed in the above described method. Then, the image is enlarged or reduced, and the values of integers are leveled such that the number of sets of four integers of the feature amount can match the number the

horizontal pixels predetermined for each category.

For an input image, the upper and lower limits of an input image are set, and the primary and secondary peripheral features from the upper and lower limits are obtained, thereby obtaining the peripheral features of the input image.

In vertical writing, the peripheral features to the n-th peripheral feature in both right and left directions. For example, a category can be compared with an input image using the primary and secondary peripheral features from the right end and the left end of an image.

FIG. 7 shows the method of computing the difference level through the continuous DP according to an embodiment of the present invention. In FIG. 7, assuming that a pattern comprising the touching characters 257 is input as an input image, the feature amount of each category stored in the dictionary is compared with the feature amount of the entire pattern comprising the touching characters 257.

The case in which the feature amount of the category 5 is compared with the feature amount of the entire pattern comprising the touching characters 257 in the feature amounts of the categories entered in the dictionary is described below. First, assuming

that the number of pixels  $dy$  is 30 in the horizontal direction of the category 5, and the peripheral feature  $F_k$  of the category 5 is entered in the dictionary as a sequence of 30 sets of four integers, these 30 sets of four integers ( $k_0, k_0', k_0'', k_0'''$ ), ( $k_1, k_1', k_1'', k_1'''$ ), ..., ( $k_{29}, k_{29}', k_{29}'', k_{29}'''$ ) are allowed to correspond to the coordinates from  $y = 0$  to  $y = y_1 = 29$ . In this example,  $k_0, k_1, \dots, k_{29}$  is the primary peripheral feature from the upper limit of the category 5 (corresponding to FIG. 6A),  $k_0', k_1', \dots, k_{29}'$  is the secondary peripheral feature from the upper limit of the category 5 (corresponding to FIG. 6B),  $k_0'', k_1'', \dots, k_{29}''$  is the primary peripheral feature from the lower limit of the category 5 (corresponding to FIG. 6C),  $k_0''', k_1''', \dots, k_{29}'''$  is the primary peripheral feature from the lower limit of the category 5 (corresponding to FIG. 6D).

In addition, assuming that the number  $dx$  of the pixels in the horizontal direction of the pattern comprising the touching characters 257 is 86, the left end LI of the pattern comprising the touching characters 257 is allowed to correspond to  $x = 0$ , and the right end RI of the pattern comprising the touching characters 257 is allowed to correspond to

x = 85. Then, the peripheral feature FI of the  
 pattern comprising the touching characters 257 is  
 extracted as a sequence of 86 sets of 4 integers.  
 These 86 sets of 4 integers (I0, I0', I0'', I0'''),  
 5 (I1, I1', I1'', I1'''), ..., (I85, I85', I85'',  
 I85''') are allowed to correspond to the coordinates  
 of x = 0 through x = x1 = 85. In this example, I0,  
 I1, ..., I85 are the primary peripheral features from  
 the upper limit of the pattern comprising the touching  
 10 characters 257. I0', I1', ..., I85' are the secondary  
 peripheral features from the upper limit of the  
 pattern comprising the touching characters 257. I0'',  
 I1'', ..., I85'' are the primary peripheral features  
 from the lower limit of the pattern comprising the  
 15 touching characters 257. I0''', I1''', ..., I85'''  
 are the secondary peripheral features from the lower  
 limit of the pattern comprising the touching  
 characters 257.

Next, when the peripheral feature FI of the  
 20 pattern comprising the category 5 on the x axis, and  
 the feature amount Fk of the category 5 on the y axis  
 are obtained, 30 elements of the peripheral feature  
 Fk of the category 5 are allowed to correspond to the  
 elements of the peripheral feature FI of the touching  
 25 characters 257. In the correspondence, the optimum



correspondence is obtained, and the position of the element on the x axis in the optimum correspondence can be defined as a candidate for the segmentation position of the touching characters 257. At this point, the accumulation value of the distance between elements is obtained, and is normalized by the weight. Then, the smallest correspondence for the normalized value can be defined as the optimum correspondence.

Assuming that the correspondence between the element of an input pattern and the element of a category is referred to as a route, the optimum route up to the current point (x, y) can be obtained by selecting the route indicating the smallest difference level in the past routes up to the current point (x, y). In the correspondence between a category and an input pattern, assuming that the order in a sequence of elements is not inverted, and no jump is made in adopting elements forming part of the sequence, the route up to the current point (x, y) is limited to the three paths as shown in FIG. 8.

Therefore, when the optimum route up to the current point (x, y) is obtained, the optimum route up to the current point (x, y) is obtained by first obtaining the optimum route up to the past point, and then selecting the route indicating the lowest

5

10

$$0 \leq x \leq x_1, \quad 0 \leq y \leq y_1$$

where  $M$  indicates a sufficiently large value

$$q(x, 1) = \min$$

$$q(x-1, 0) + 2d(x, 0) \dots (4)$$

$$q(x, y) = \min$$

20

$$q(x-1, y-1) + 2d(x, y) \dots (7)$$

$$q(x-1, y-2) + 2d(x, y-1) + d(x, y)\} \quad \dots(8)$$

25

$$d(x, y) = \sum_{n=1, 2, \dots} |I P_n, up(x) - K_n, up(y)|$$

$$+ |IP_n, \text{down}(x) - K_n, \text{down}(y)| \quad \dots (17)$$

where  $IP_n, \text{up}(x)$  indicates the  $n$ -th peripheral feature from the upper limit of the input image at the point  $x$ ,  $IP_n, \text{down}(x)$  indicates the  $n$ -th peripheral feature from the lower limit of the input image at the point  $x$ ,  $K_n, \text{up}(y)$  indicates the  $n$ -th peripheral feature from the upper limit of the category at the point  $y$ , and  $K_n, \text{down}(y)$  indicates the  $n$ -th peripheral feature from the lower limit of the category at the point  $y$ .

The distance  $d(x, y)$  can be defined by an Euclidian distance, etc.

In FIG. 8, assuming that the accumulation value of the difference level to the point  $P_1$  is  $q(x-2, y-1)$ , the accumulation value of the difference level to the point  $P_2$  is  $q(x-1, y-2)$ , the accumulation value of the difference level to the point  $P_3$  is  $q(x-1, y-1)$ , the accumulation value of the difference level to the point  $P_4$  is  $d(x-1, y)$ , the accumulation value of the difference level to the point  $P_5$  is  $d(x, y-1)$ , and the accumulation value of the difference level to the point  $P_6$  is  $d(x, y)$ , the equation (6) corresponds to obtaining the accumulation value  $q(x, y)$  at the difference level to the point  $P_6$  through the route  $P_1 \rightarrow P_4 \rightarrow P_6$  shown in FIG. 8, the equation (7)

corresponds to obtaining the accumulation value  $q(x, y)$  at the difference level to the point P6 through the route  $P3 \rightarrow P6$  shown in FIG. 8, and the equation (8) corresponds to obtaining the accumulation value  $q(x, y)$  at the difference level to the point P6 through the route  $P2 \rightarrow P5 \rightarrow P6$  shown in FIG. 8.

The weight  $g(x, y)$  corresponding to the accumulation value  $q(x, y)$  can be obtained by the gradual change equations (9) through (16) of the weight.

Gradual change equation of weight

$$g(-1, y) = g(0, y) = 0 \quad \dots(9)$$

$$g(x, 0) = 2 \quad \dots(10)$$

$$g(x, 1) = \{g(x-2, 0) + 3 \quad \dots(11)$$

$$g(x-1, 0) + 2 \quad \dots(12)$$

$$g(x, 9) + 1\} \quad \dots(13)$$

$$g(x, y) = \{g(x-2, y-2) + 3 \quad \dots(14)$$

$$g(x-1, y-1) + 2 \quad \dots(15)$$

$$g(x-1, y-2) + 3\} \quad \dots(16)$$

where the gradual change equations (9) through (16) of weight respectively correspond to the gradual change equations (1) through (8) of accumulation values.

The accumulation value  $q(x, y)$  of a difference

level and the weight  $g(x, y)$  are obtained by the equations (1) through (16), the difference level  $D(x, y)$  between an input image for the optimum route to the point  $(x, y)$  and a category can be obtained by the equation (17).

$$D(x, y) = q(x, y) / g(x, y) \quad \dots(18)$$

Using the above described equation, the difference level  $D(x, y)$  between the input image for the optimum route to the point  $(x, y)$  and the category can be obtained for each point  $(x, y)$  shown in FIG. 7. To obtain the difference level  $D(x, y)$  of the current point  $(x, y)$  it is necessary to obtain the difference level of the past point. Therefore, the value of  $M$  is set by the equation (1) as the difference level corresponding to the point of  $x = -1$  and  $x = 0$ . Then, the difference level  $D(x, y)$  is obtained in the order of  $D1 \rightarrow D2 \rightarrow \dots \rightarrow D6 \rightarrow \dots \rightarrow D7 \rightarrow D8 \rightarrow \dots \rightarrow D12 \rightarrow \dots \rightarrow D37 \rightarrow D38 \dots \rightarrow D42$ .

In addition, for example, when the difference level  $D28$  of the current point  $(x, y)$  is obtained, the route to the current point  $(x, y)$  can be any of the three routes  $R1$  through  $R3$ . By substituting the accumulation value  $q(x, y)$  in the equation (6) and the weight  $g(x, y)$  in the equation (14) for the equation (18), the difference level  $D(x, y)$  to the

current point  $(x, y)$  through the route  $R1$  can be obtained. Similarly, by substituting the accumulation value  $q(x, y)$  in the equation (7) and the weight  $g(x, y)$  in the equation (15) for the equation (18), the  
 5 difference level  $D(x, y)$  to the current point  $(x, y)$  through the route  $R2$  can be obtained. Furthermore, by substituting the accumulation value  $q(x, y)$  in the equation (8) and the weight  $g(x, y)$  in the equation (16) for the equation (18), the difference level  $D(x,$   
 10  $y)$  to the current point  $(x, y)$  through the route  $R3$  can be obtained. Therefore, in the three routes  $R1$  through  $R3$ , the difference level  $D28$  of the current point  $(x, y)$  can be obtained by selecting the route indicating the lowest difference level. When one of  
 15 the three routes  $R1$  through  $R3$  to the current point  $(x, y)$  is selected, the selected route is entered.

FIG. 9 is a flowchart of the method of computing the difference level using the continuous DP according to an embodiment of the present invention. In FIG.  
 20 9, the initializing process is performed first (step S21). In the initializing process, in the range of  $0 \leq y \leq y1$ ,  $q(-1, y) = q(0, y) = M$  is set, and  $g(-1, y) = g(0, y) = 0$  is set. Then,  $x = 1$  is set (step S22), and  $q(x, 0) = 2d(x, 0)$ , and  $g(x, 0) = 2$  is  
 25 set (step S23). Then, for  $y = 1$ , the accumulation

value  $q(x, y)$  is obtained by the equations (3) through (5), and the weight  $g(x, y)$  corresponding to the accumulation value  $q(x, y)$  is obtained by the equations (11) through (13). In addition, in the  
 5 range of  $2 \leq y \leq y_1$ , the accumulation value  $q(x, y)$  is obtained by the equations (6) through (8), and the weight  $g(x, y)$  corresponding to the accumulation value  $q(x, y)$  is obtained by the equations (14) through (16) (step S24). The above described process  
 10 is repeated with the value of  $x$  increased by 1 (step S25) until  $x$  equals  $x_1$  (step S26).

In the above described process, the optimum route to the point  $(x, y)$  and the corresponding difference level can be obtained in the range of  $0 \leq x \leq 1$ , and  
 15  $0 \leq y \leq y_1$ . When the optimum route to the point  $(x, y)$  is obtained, the starting point  $(x_0, y_0)$  corresponding to the point  $(x, y)$  can be obtained by inversely tracing the route. The correspondence can be represented as follows.

20  $x_0 = \text{Stc}(x, y)$

$y_0 = \text{Sty}(x, y)$

As shown in FIG. 20, the point  $(st, 0)$  corresponding to the leftmost point  $L_k$  of the category  
 5 is searched for by inversely tracing the optimum  
 25 route to the point  $(x, y_1)$  corresponding to the

rightmost point  $R_k$  of the category 5. When the point  $(st, 0)$  corresponding to the leftmost point  $L_k$ , the value  $st$  on the  $x$  axis is defined as the starting point of the category 5 at the coordinate  $x$ .

5        As described above, the comparison result of the category  $K$  and the coordinate  $x$  can be obtained as follows with the difference level defined as  $Sc(x, K)$  and the starting point as  $St(x, K)$ .

$$Sc(x, K) = D(x, dy - 1)$$

10         $St(x, K) = Stx(x, dy - 1)$

15        In the above described process, when the difference level is set smallest with the rightmost point  $R_k$  of the category 5 corresponding to the point  $x$  in the horizontal direction of the touching characters 257, the point  $st$  in the horizontal direction of the touching characters 257 corresponding to the leftmost point  $L_k$  of the category 5, and the corresponding difference level can be obtained.

20        The above described process is performed on the pattern comprising the touching characters 257 for all categories  $K$  to be recognized. For example, assuming that the category  $K$  to be recognized is 0 through 9, the above described process is performed for all categories 0 through 9. Then, in the range of  $0 \leq x$   
 25         $\leq x_1$ , the starting point  $St(x, K)$  and the

004250" 0424560



corresponding difference level  $Sc(x, K)$  are obtained for each category  $K$ .

FIG. 11 shows a part of the result of computing for each category the starting point and the corresponding difference level according to an embodiment of the present invention. In the example shown in FIG. 11, only the range of  $47 \leq x \leq 72$  is shown, and other ranges of  $x$  are omitted. In addition, when the difference level  $sc$  is equal to or larger than a predetermined threshold, it is represented by  $xx$ . In FIG. 11, for example, when  $x = 60$ , the difference level  $sc$  is not smaller than a predetermined threshold for the categories 0, 1, and 4 although the starting point  $st$  is set to any point on the  $x$  axis. For the category 2, the difference level  $sc$  is the lowest when the rightmost point of the category 2 is set to the point  $x = 60$ , and the corresponding difference level  $sc = 67$  by setting the starting point  $st = 40$  (in this case, the operation corresponds to setting the leftmost point of the category 2 at the point of  $x = 40$ ). For example, for the category 5, the difference level  $sc$  is the lowest when the rightmost point of the category 5 is set to the point of  $x = 60$ , and the corresponding difference level  $sc$  is 30 by setting the starting point  $st$  to 33.

FIG. 12 shows the method of searching for the route of a segmentation position from the computation result shown in FIG. 11. In FIG. 12, assuming that the category K to be recognized is 0 through 9, and the number w1 of pixels in the horizontal direction of the pattern of the touching characters 257 to be segmented is 86, the starting point st and the corresponding difference level sc are obtained for all categories 0 through 9 in the range of  $0 \leq x \leq x_1 = 85$ . In this case, for example, the point of  $x = 85$  at the rightmost point of the pattern of the touching characters 257 is considered (hereinafter the point is referred to as an initial base point). Then, it is checked whether or not the difference level sc equal to or lower than the threshold TH can be detected in the difference levels sc corresponding to the point of  $x = 85$ . In this example, if the threshold TH is set to, for example, 35, then the difference level sc of the category 7 is 25, thereby detecting the category 7 with the difference level sc equal to or smaller than the threshold TH of 35. When the category 7 is detected at the point of  $x = 85$ , the starting point corresponding to the category 7 at the point of  $x = 85$  is checked. As a result, since the starting point st of the category 7 at the point  $x =$

85 is 62, the segmentation position of the pattern of the touching characters 257 is obtained from the starting point  $st = 62$ . When the segmentation position of the rightmost point of the pattern corresponding the category 7 is set to  $x = 85$ , and when the segmentation position of the leftmost point of the pattern corresponding the category 7 is set to  $x = 62$ , the starting point  $st = 62$  indicates the lowest difference level  $sc$ . In addition, the corresponding difference level  $sc$  is 25. Therefore, the next segmentation position of the pattern of the touching characters 257 is assumed to be within the range back from  $x = st = 62$  by a predetermined value of  $th$ . For example, if the predetermined value  $th = 2$ , the search range of the next segmentation position is set to  $x = 60$  through 62, and it is checked whether or not the difference level  $sc$  equal to or lower than the threshold  $TH$  exists in the difference levels  $sc$  corresponding to the points  $x = 60$  through 62. Since the difference level  $sc$  of the category 5 at the point  $x = 60$  is 30, the category 5 of the difference level  $sc$  equal to or lower than the threshold  $TH = 35$  is detected. When the category 5 is detected at the point  $x = 60$ , the coordinate  $x = 60$  is defined as the next segmentation position of the pattern of the

touching characters 257 (hereinafter the point is referred to as a base point). The path P1 connecting the point of the initial segmentation position where  $x = 85$  with the point of the next segmentation position where  $x = 60$  is generated.

When the path P1 is generated, the starting point st corresponding to the category 5 at the point  $x = 60$  is checked. As a result, it is proved that the starting point st of the category 5 at the point  $x = 60$  is 33, the next segmentation position of the touching characters 257 is obtained from the starting point st = 33. Accordingly, the search range for the next segmentation position is  $x = 31$  through 33, and it is checked whether or not the difference level sc equal to or lower than the threshold TH exists in the difference levels sc corresponding to the point  $x = 31$  through 33. Since the difference level sc of the category 2 at the point  $x = 31$  is 35, the category 2 of the difference level sc equal to or lower than the threshold TH = 35 is detected. When the category 2 at the point  $x = 31$  is detected, the coordinate  $x = 31$  is defined as the next segmentation position of the touching characters 257. In addition, the path P2 connecting the point at the segmentation position where  $x = 60$  to the point at the next segmentation

position where  $x = 31$  is generated.

When the path P2 is generated, the starting point st corresponding to the category 2 at the point  $x = 31$  is checked. As a result, since it is proved that the starting point st of the category 2 at the point  $x = 31$  is 7, the next segmentation position of the pattern of the touching characters 257 is obtained from the starting point st = 7. Assuming that there is no pattern corresponding to the categories 0 through 9 in the range before  $x = 7$ , the segmentation position of the pattern of the touching characters 257 is defined as the point  $x = 7$  (hereinafter the point is referred to as a source point). Then, the path P2 connecting the point of the segmentation position where  $x = 31$  to the point of the next segmentation position where  $x = 7$  is generated, thereby terminating the segmenting process.

In the above described process, the pattern of the touching characters 257 can be sectioned at the boundary between 2 and 5, and 5 and 7. When the paths P1 through P3 are obtained for the pattern of the touching characters 257, the segmentation positions obtained by performing the segmenting process through the route  $P1 \rightarrow P2 \rightarrow P3$  can be evaluated by considering the weight for the paths P1 through P3. As the weight

of the paths P1 through P3, the difference level sc between each of the patterns segmented corresponding to the paths P1 through P3 and the category corresponding to each of the patterns can be used.

5 For example, the weight of the path P1 is 25 obtained from the difference level sc of the category 7 at the point where  $x = 85$ , the weight of the path P2 is 30 obtained from the difference level sc of the category 5 at the point where  $x = 60$ , and the weight of the  
10 path P3 is 35 obtained from the difference level sc of the category 2 at the point where  $x = 31$ . When the weight of the paths P1 through P3 is obtained, the value  $v = 90 / 3 = 30$  obtained by dividing the total weight  $q = 25 + 30 + 35 = 90$  of the paths P1 through  
15 P3 by the number  $b = 3$  of paths P1 through P3 is defined as a segmentation position evaluation value.

FIG. 13 is a flowchart of the method of computing the segmentation position according to an embodiment of the present invention. In FIG. 13, the initial  
20 base point selecting process is performed first (step S31). In this initial base point selecting process, the difference level Sc ( $dx - 1, K$ ) entered corresponding to the coordinate  $x = dx - 1$  of the rightmost point of the input pattern is considered.  
25 The categories K are arranged in order from smallest

to largest in difference level  $Sc(dx - 1, K)$ , and  $m$  smallest categories in difference level  $Sc(dx - 1, K)$  are selected from a set of categories  $K$ . Assuming that the  $m$  smallest categories are  $K_1, K_2, \dots, K_m$ ,  
 5 the initial base point is defined as  $(dx - 1, K_1), (dx - 1, K_2), \dots, (dx - 1, K_m)$ . The characters  $dx$  indicate the number of pixels in the horizontal direction of an input pattern.

Then, a paths generating process is performed  
 10 (step S32). For each initial base point in this path generating process, the correspondence between an input image and each category is regarded as a path connecting the starting point and the end point, and the difference level of the correspondence is defined  
 15 as the weight of a path. In addition, the value of a category is added to the path.

FIG. 14 is a flowchart of the path generating process according to an embodiment of the present invention. In FIG. 14, for the coordinate  $x$  and the  
 20 initial base point  $(x, K)$  corresponding to the category  $K$  (step S41), the difference level  $sc = Sc(x, K)$ , and the starting point  $sc = St(x, K)$  are checked (step S42). Then, for  $x = st$ , the base point is searched for (step S43). A base point refers to  
 25 a point where  $Sc(x, K_i)$  indicates the smallest value

in the points where  $Sc(x, Ki) < TH$  for  $(x, Ki)$ , and the value of  $St(x, Ki)$  is constant in all categories  $Ki$  in the range  $st - th \leq x \leq st$ . If the number of base points is 0 (step S44), then a path having a

5 starting point  $st$ , an end point  $x$ , weight  $sc$ , and a category  $K$  is entered (step S45), thereby terminating (returning) the process. On the other hand, if the number of base points is  $a$ , and the base points are  $(xi, ki)$  ( $i = 1, \dots, a$ ) (step S44), then a path

10 having a starting point  $xi$ , an end point  $x$ , weight  $sc$ , and a category  $K$  is entered (step S46). Then, back in step S41, the similar process is performed for each base point.

FIG. 15 is a flowchart of the base point

15 searching process according to an embodiment of the present invention. In FIG. 15, BPcheck, BPscore, BPend, and  $a$  are initialized (step S51). Each of the BPcheck, BPscore, and BPend is a  $dx$  array. BPcheck indicates whether or not the coordinate  $x$  has been

20 checked, and the initial value is all 0. BPscore contains the value of the difference level  $sc$ , and the initial value is all -1. BPend contains a coordinate, and the initial value is all  $st$ . The integer  $a$  indicates the number of detected base points, and the

25 initial value is 0.



Next, K is set to 0 (step S52), and x is set to st (step S54) when  $K < \max$  (step S53) where max indicates the number of categories K to be recognized. When the conditions of  $x \geq st - th$  and  $x \geq 0$  (step S55) are not met, the value of K is increased by 1 (step S62), and control is returned to step S53. When  $x \geq st - th$  and  $x \geq 0$  (step S55), it is checked whether or not  $sc(x) = Sc(x, K)$ ,  $st(x) = St(x, K)$ , and  $sc(x) < TH$  (step S56). If the condition  $sc(x) < TH$  is not met, x is decreased by 1 (step S61), and control is returned to step S55. On the other hand, if  $sc(x) < TH$ , it is determined whether or not  $BPcheck(st(x)) > 0$  (step S57). If the condition  $BPcheck(st(x)) > 0$  is not met, then  $BPcheck(st(x)) = 1$ , the value of a is increased by 1 (step S58), and control is passed to step S60. On the other hand, if  $BPcheck(st(x)) > 0$ , then it is determined whether or not the conditions  $sc(x) < BPscore(st(x))$  or  $sc(x) = BPscore(st(x))$  and  $x < BPend(st(x))$  are met (step S59). If the conditions in step S59 are not met, control is passed to step S61. On the other hand, if the conditions in step S59 are met, then  $BPscore(st(x)) = sc(x)$ ,  $BPend(st(x)) = x$  (step S60). The above described process is performed on all categories K to be recognized for the coordinate x

satisfying the conditions  $x \geq st - th$ , and  $x \geq 0$ .

FIG. 16 shows an example of generating a path according to an embodiment of the present invention. In FIG. 16, for example, it is assumed that four  
5 initial base points B1 through B4 are selected at the point where  $x1 = dx - 1$ . As a result of detecting the base points B5 and B11 for the initial base point B1, the route of two paths  $P19 \rightarrow P20$  is obtained. As a result of detecting the base points B6, B9, and B13  
10 for the initial base point B2, the route of three paths  $P17 \rightarrow P18 \rightarrow P13$  is obtained. As a result of detecting the base points B7, B9, and B13 for the initial base point B3, the route of three paths  $P11 \rightarrow P12 \rightarrow P13$  is obtained. As a result of detecting the  
15 base points B8, B10, and B12 for the initial base point B4, the route of three paths  $P14 \rightarrow P15 \rightarrow P16$  is obtained.

Each of the paths P11 through P20 is assigned an attribute comprising a starting point, an end point,  
20 weight, and a category. For example, the starting point  $xf$ , the end point  $x1$ , the difference level  $sc$  of the category corresponding to the initial base point B1, and the category corresponding to the initial base point B1 are assigned as attributes of  
25 the path P11. In addition, the starting point  $xd$ , the

end point  $x_f$ , the difference level  $sc$  of the category corresponding to the initial base point  $B_7$ , and the category corresponding to the initial base point  $B_7$  are assigned as attributes of the path  $P_{12}$ .

5        Then, the optimum route is searched for (step S33). In searching the optimum path, the optimum route is searched for in a set of paths generated in the above described processes. First, for each coordinate  $x$ , the paths  $P_i$  having the starting points  
10        at the coordinate  $x$  are listed. At this time, for these paths  $P_i$ , the functions for correspondence among a starting point, an end point, weight, and a category are  $st(P_i)$ ,  $ed(P_i)$ ,  $sc(P_i)$ , and  $ca(P_i)$ . In addition, assuming that the accumulation value of the  
15        weight at the coordinate  $t (> x)$  is  $q(t)$ , and the value indicating the number of paths passed through is  $b(t)$ , the following equation is set.

$$(q(ed(P_i)) + sc(P_i)) / (b(ed(P_i)) + 1) \quad \cdots (19)$$

20        The path  $P_i$  indicating the minimum value is selected, and the path  $P_i$  is set as  $P_i = \arg(x)$ .

Then, the following equations are set.

$$q(x) = q(ed(P_i = \arg(x))) + sc(P_i = \arg(x)) \quad \cdots (20)$$

$$b(x) = b(ed(P_i = \arg(x))) + 1 \quad \cdots (21)$$

25        The following evaluation  $v(x)$  is computed for the source point in each coordinate after the above

described computation is performed for all coordinates.

$$v(x) = q(x) / b(x) \quad \dots(22)$$

where a source point refers to a point where one  
 5 or more paths having the coordinate  $x$  as a starting  
 point exist, and where a path does not have the  
 coordinate  $x$  as an end point. The source points are  
 arranged in order using the evaluation value  $v(x)$ ,  
 and the coordinate indicating the smallest evaluation  
 10 value  $v(x)$  is defined as  $x = \text{Origin}$ . When Origin is  
 obtained, a sequence of paths for the shortest route  
 can be obtained by inversely tracing the paths from  
 the Origin. Then, the end point and the category  
 assigned to the paths can be provided as a section  
 15 point and a character recognition result respectively.

For example, in FIG. 16, the base point B9 can  
 be reached through two routes  $P11 \rightarrow P12$  and  $P17 \rightarrow P18$ .  
 In this case, the computation is performed by the  
 equation (19) up to  $t = x_d$ , and a smaller resultant  
 20 value is selected. Assuming that the route  $P11 \rightarrow P12$   
 is selected, the route  $P19 \rightarrow P20$  is obtained as a  
 route to the source point B11, the route  $P14 \rightarrow P15 \rightarrow$   
 $P16$  is obtained as a route to the source point B12,  
 and the route  $P11 \rightarrow P12 \rightarrow P13$  is obtained as a route  
 25 to the source point B13. When the source points B11

through B13 are obtained, the smallest evaluation  $v$  ( $x$ ) obtained by the equation (22) is selected. If the source point B12 is selected, the coordinate  $x_a$  corresponding to the source point B12 is defined as Origin. By inversely tracing the paths P14 through P16 from Origin, the section points  $x_c$  and  $x_e$  can be determined. In addition, the categories assigned to the paths P14 through P16 can be recognition results at respective segmentation positions.

As described above, according to the present invention, the entire image can be compared with each category for the character touching pattern in which each character cannot be clearly segmented from each other based on image features. Therefore, the category and the segmentation position can be made consistent in the obtained comparison result, and a combination of matching category and segmentation position can be obtained, thereby correctly segmenting and recognizing a character. In addition, by combining the segmenting process through comparison with a category and the character recognizing process, the character recognizing process can be performed with higher precision.

FIG. 17 is a block diagram of the configuration of an information processing apparatus for realizing

the pattern segmenting process and the pattern recognizing process according to an embodiment of the present invention by software. In FIG. 17, 11 is a central processing unit (CPU) for performing the entire process, 12 is read-only memory (ROM), 13 is random-access memory (RAM), 14 is a communications interface, 15 is a communications network, 16 is an input/output interface, 17 is a display for displaying document data, etc., 18 is a printer for printing document data, 19 is memory for temporarily storing document data, etc. read from a scanner 20 for reading an input image, etc., 21 is a keyboard, 22 is a pointing device such as a mouse, etc., 23 is a driver for driving a storage medium, 24 is a hard disk, 25 is an IC memory card, 26 is a magnetic tape, 27 is a floppy disk, 28 is an optical disk such as CD-ROM, DVD-ROM, etc., and 29 is a path.

A program for segmenting and recognizing a pattern, the feature amount of a category, etc. can be stored in a storage medium such as the hard disk 24, the IC memory card 25, the magnetic tape 26, the floppy disk 27, the optical disk 28, etc. By reading a program for segmenting and recognizing a pattern and the feature amount of a category from the storage medium to the RAM 13, a pattern can be segmented and

recognized. In addition, a program for segmenting and recognizing a pattern can be stored in the ROM 12.

Furthermore, a program for segmenting and recognizing a pattern, the feature amount of a category, the feature amount of an input image, etc. can be retrieved from the communications network 15 through the communications interface 14. As a communications network 15 connected to the communications interface 14, a radio communications network, for example, a LAN (local area network), a WAN (wide area network), Internet, an analog telephone network, a digital telephone network (ISDN: integral service digital network), a PHS (personal handy system), satellite communications, etc., can be used.

When a program for segmenting or recognizing a pattern is activated, the CPU 11 obtains the feature amount of a category from a storage medium such as the hard disk 24, or the communications network 15, etc. In addition, from an input image read through the scanner 20, or from an input image transmitted through the communications network 15, the feature amount of an input image is extracted. While changing a corresponding portion of the feature amount of an input image against the feature amount of a category, the feature amount of a category is compared with the

feature amount of an input image. As a result of the comparison, when the portion corresponding to the feature amount of the category is obtained from the input image, the portion corresponding to the feature amount of the category is defined as the segmentation position of the input image. When the segmentation position of the input image is obtained, the category used in the comparison can be defined as a recognition result of a pattern segmented from the input image. Furthermore, to obtain a recognition result, a pattern segmented from the input image can be recognized. When a recognition result is obtained, the recognition result can be output to the display 17 and the printer 18, or transmitted through the communications network 15.

FIG. 18 shows the method of providing a software program, etc. for segmenting and recognizing a pattern according to an embodiment of the present invention. A program, etc. is provided by an optional method in the three following methods.

(a) A program is provided as installed in an information processing apparatus 30 of a computer, etc. shown in FIG. 17. In this case, a program, etc. is, for example, pre-installed before delivery.

(b) A program is provided as stored in a



portable storage medium 31. In this case, a program, etc. stored in the portable storage medium 31 is installed in an external storage device of the information processing apparatus 30 of a computer, etc.

(c) A program is provided from a server 33 in a network 32. In this case, the program, etc. can be basically obtained by the information processing apparatus 30 of a computer, etc. downloading the program, etc. stored in the server 33.

As described above, according to the present invention, a process of segmenting a pattern from an image can be performed with the entire form and the structure of a category as well as the outline or the unevenness of a pattern taken into account by segmenting a pattern based on a comparison result between the feature amount of a category and the feature amount of an image, thereby improving the pattern segmentation precision. Furthermore, a pattern corresponding to the feature amount of a category can be collectively segmented from an image, thereby preventing the pattern corresponding to one category from being sectioned at a number of points.

Furthermore, according to an aspect of the present invention, the comparison precision between

the feature amount of a category and the feature amount of a character pattern of a character string image can be maintained even when distortion or deformation arises in the character string image by comparing the category with the character string image with both ends of the category corresponding to various points of the character string image without fixing both ends of the category to both ends of the character string image.

In addition, according to another aspect of the present invention, by allowing one end of a category to correspond to the coordinate of the element of a character string image, and by entering in a table the coordinate of the element of the character string image corresponding to another end of the category, the segmentation position of the character string image is determined, and the next segmentation position of the character string image can be easily obtained from the table, thereby efficiently extracting another character area from the character string image.

According to a further aspect of the present invention, it can be determined whether or not a segmentation position has been correctly segmented by checking whether or not an area not corresponding to

any category to be recognized. Therefore, even when a plurality of segmentation areas are obtained from an image, the optimum segmentation position can be obtained from the plurality of areas.

5           According to a further aspect of the present invention, by separately setting the feature amount for segmentation of a category and the feature amount for recognition of a category, a pattern can be segmented using the feature amount for segmentation  
10           of a category, and the segmented pattern can be recognized using the feature amount for recognition of a category. Therefore, it can be determined whether or not the pattern can be correctly recognized using different feature amounts. In addition, when  
15           a segmenting process is performed, the feature amount appropriate for segmentation can be used, and when a recognizing process is performed, the feature amount appropriate for recognition can be used, thereby improving the segmentation precision and the  
20           recognition precision.

          According to a further aspect of the present invention, when a pattern is segmented using the feature amount for segmentation of a category, the category is defined as a recognition result of the  
25           pattern, thereby obtaining the recognition result of

the pattern only by segmenting the pattern from an image, and shortening the time taken to obtain a recognition result of a pattern.

004250 042560

What is claimed is:

- 09577340-052400  
004250" 04E/4560
1. A pattern segmentation apparatus, comprising:  
a feature amount extraction unit extracting a  
5 feature amount of an image;  
a feature amount setting unit setting a feature  
amount of a category;  
a feature amount comparison unit comparing the  
feature amount of the category with the feature amount  
10 of the image; and  
a segmentation unit segmenting a portion  
corresponding to the feature amount of the category  
from the image.
  - 15 2. The apparatus according to claim 1, wherein  
said feature amount comparison unit comprises a  
correspondence generation unit generating  
correspondence between the feature amount of the  
category and the feature amount of the image, and  
20 compares the feature amount of the category with the  
feature amount of the image.
  3. The apparatus according to claim 2, wherein  
said feature amount comparison unit comprises:  
25 a difference level computation unit

comparing a difference level between the feature amount of the category and the feature amount of the image corresponding to the correspondence; and

an optimum correspondence extraction unit  
5 extracting optimum correspondence indicating a lowest difference level from the correspondence, wherein

said segmentation unit segments a portion indicating a difference level corresponding to the optimum correspondence equal to or lower than a  
10 predetermined value.

4. The apparatus according to claim 3, further comprising:

a combination unit generating a combination of  
15 segmentation areas by said segmentation unit such that each pattern segmented by said segmentation unit can correspond to any category to be recognized; and

a segmentation area determination unit  
determining a segmentation area of the image by  
20 prioritizing a combination indicating a smaller difference level accumulation value in the combinations.

5. An pattern segmentation apparatus, comprising:  
25 a feature amount extraction unit extracting a

09577340-052400

feature amount of a character string image as a sequence of elements in a character string array direction;

5 a feature amount setting unit setting a feature amount of a category in a category array direction;

a correspondence unit corresponding a last element in the sequence of the elements of the category with each element of the character string image;

10 a search unit searching for an element of the character string image corresponding to a first element of the sequence of the elements of the category by allowing an sequence of remaining elements of the category with the element of the character string image for correspondence of the last element  
15 in the sequence of the elements of the category;

a difference level computation unit computing a difference level between the character string image and the category corresponding to each other in the  
20 sequence of the elements; and

a discrimination unit discriminating a segmentation position of a character from the character string image based on the difference level.

25 6. The apparatus according to claim 5, wherein

said difference level is obtained from an accumulation result of a distance between elements from the first element to the last element in the sequence of the elements of the category.

5

7. The apparatus according to claim 6, wherein said search unit makes correspondence of a current element in the correspondence of past elements based on the correspondence indicating the smallest accumulation value of the distance between elements.

10

8. The apparatus according to claim 5, further comprising:

15

an entry unit entering a set of an element of the character string image corresponding to the first element of the sequence of the elements of the category and a corresponding difference level for all elements in the character string image array direction;

20

a search unit detecting a difference level indicating a value equal to or smaller than a predetermined value in difference levels specified by each element corresponding to the segmentation position of the character string image;

25

an obtaining unit obtaining the element of the

004250-04E4250





difference level assigned to the path;

a selection unit selecting a combination of the paths based on the evaluation result; and

5 a section point determination unit determining a coordinate assigned to a path selected by said selection unit as a section point of the character string image.

10 10. The apparatus according to claim 9, further comprising

a recognition result output unit defining a category assigned to a path selected by said selection unit as a recognition result of a pattern sectioned at the section point.

15

11. A method of segmenting a pattern, comprising:

setting a feature amount of a category;

searching for an area corresponding to the feature amount of the category in an image; and

20 segmenting an area obtained in the searching process from the image.

12. The method according to claim 11, wherein

25 said feature amount of the category is compared with the entire feature amount of the image in a

continuous DP method.

13. The method according to claim 11, wherein  
said feature amount is peripheral features up to  
5 an n-th ( $n \geq 1$ ) peripheral feature.

14. The method according to claim 11, wherein:  
every pattern segmented from the image are  
associated with any of the categories to be  
10 recognized;

a combination of a category to be recognized and  
a corresponding pattern indicating a lowest total  
difference level is selected;

15. A method of segmenting a pattern, comprising:  
segmenting a first segmentation area  
corresponding to a feature amount of a category from  
an image; and

changing the first segmentation area when a  
20 second segmentation area cannot be segmented  
corresponding to a feature amount of a category from  
remaining areas of the image.

16. A character segmenting method, comprising:  
25 extracting a feature amount of a character string





feature amount of a category;

feature amount comparison means for comparing the feature amount of the category with the feature amount of the image; and

5        segmentation means for segmenting a portion corresponding to the feature amount of the category from the image.

21. An pattern segmentation apparatus, comprising:

10        feature amount extraction means for extracting a feature amount of a character string image as a sequence of elements in a character string array direction;

15        feature amount setting means for setting a feature amount of a category in a category array direction;

20        correspondence means for corresponding a last element in the sequence of the elements of the category with each element of the character string image;

25        search means for searching for an element of the character string image corresponding to a first element of the sequence of the elements of the category by allowing an sequence of remaining elements of the category with the element of the character

004250" 04E2400

5

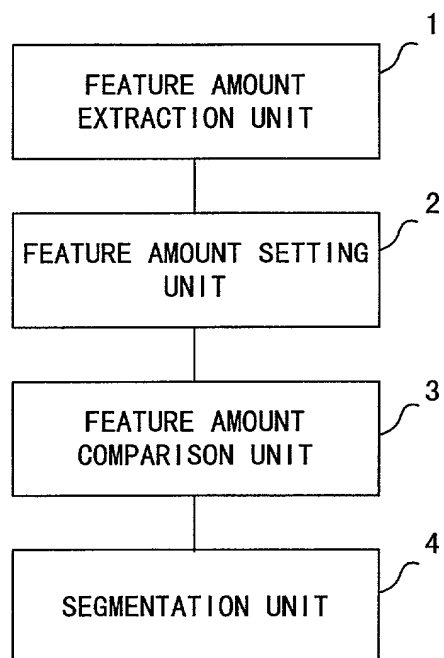
10

discrimination means for discriminating a segmentation position of a character from the character string image based on the difference level.

**Abstract of the Disclosure**

5 A pattern segmentation apparatus and a pattern  
recognition apparatus can improve the segmentation  
precision of a character touching pattern. The  
pattern segmentation apparatus includes a feature  
amount extraction unit for extracting the feature  
amount of an image, a feature amount setting unit for  
setting the feature amount of a category, a feature  
10 amount comparison unit for comparing the feature  
amount of the category with the feature amount of the  
image, and a segmentation unit for segmenting a  
portion corresponding to the feature amount of the  
category from the image based on the comparison  
15 result.





F I G. 1

FIG. 2A

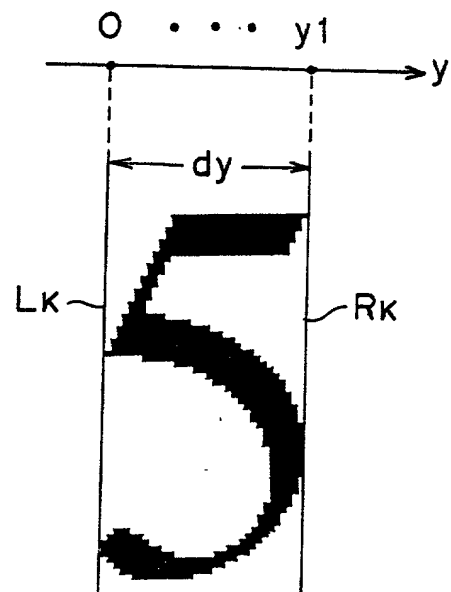
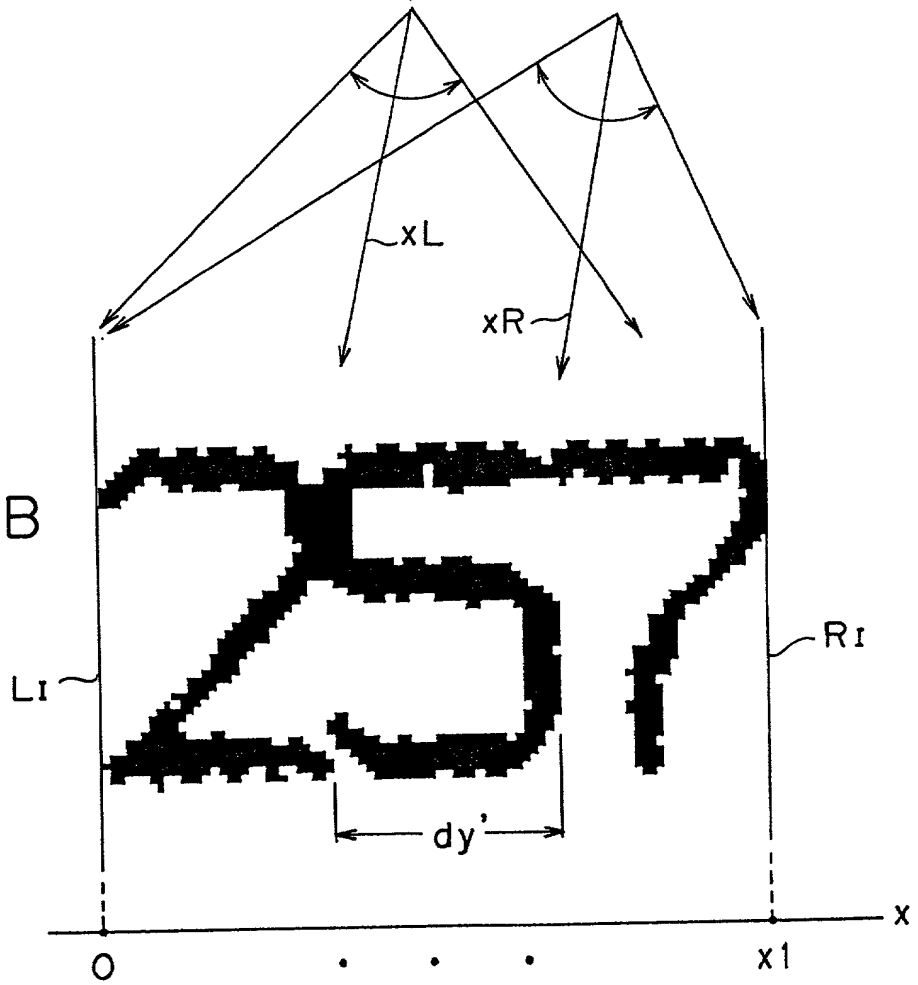


FIG. 2B



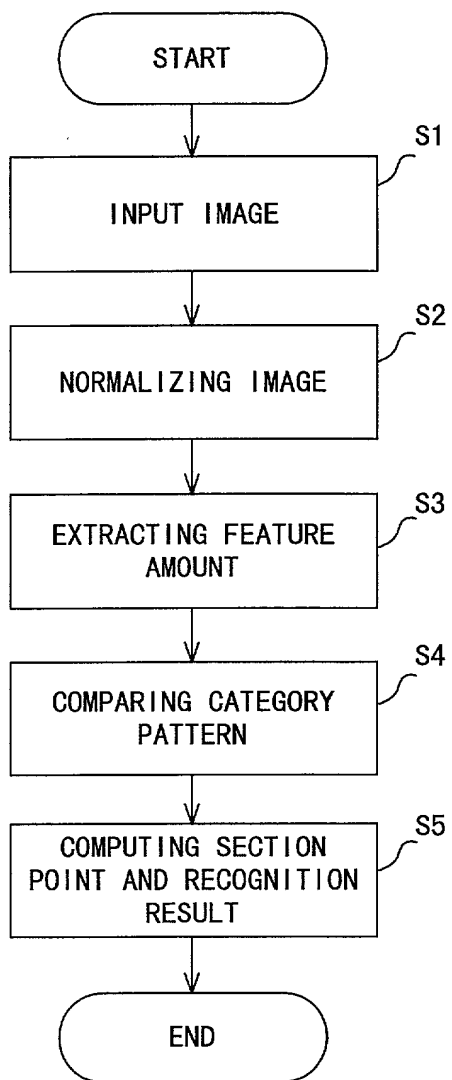


FIG. 3

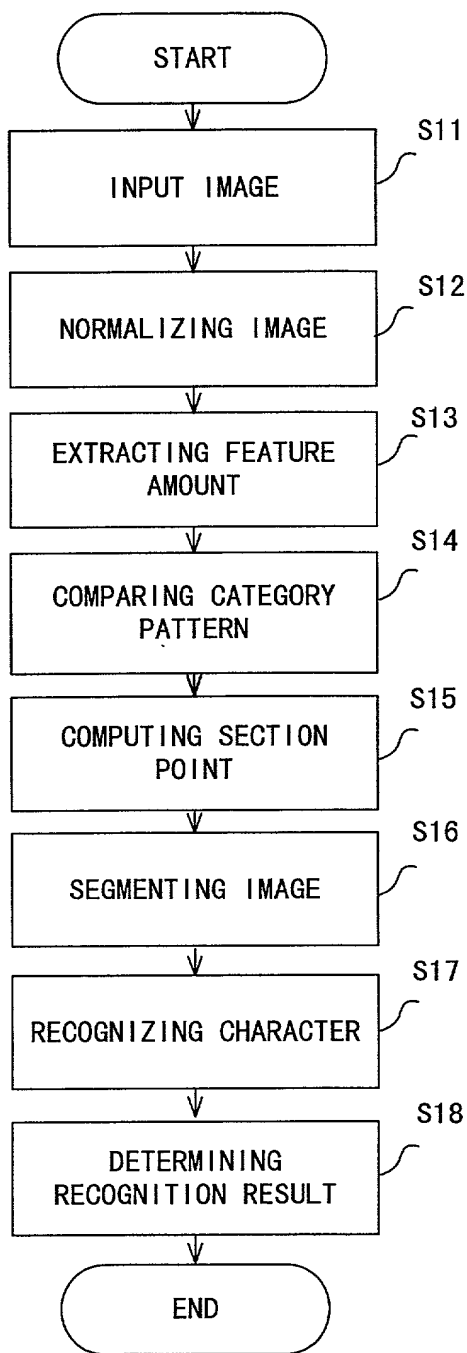


FIG. 4

FIG. 5

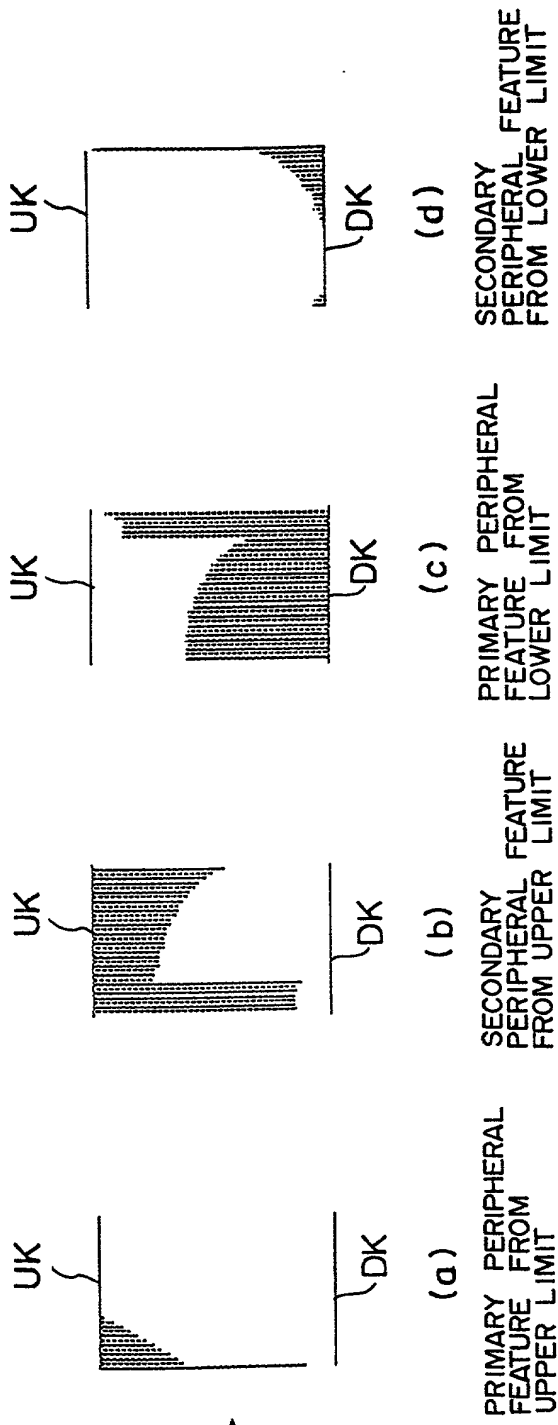


FIG. 6

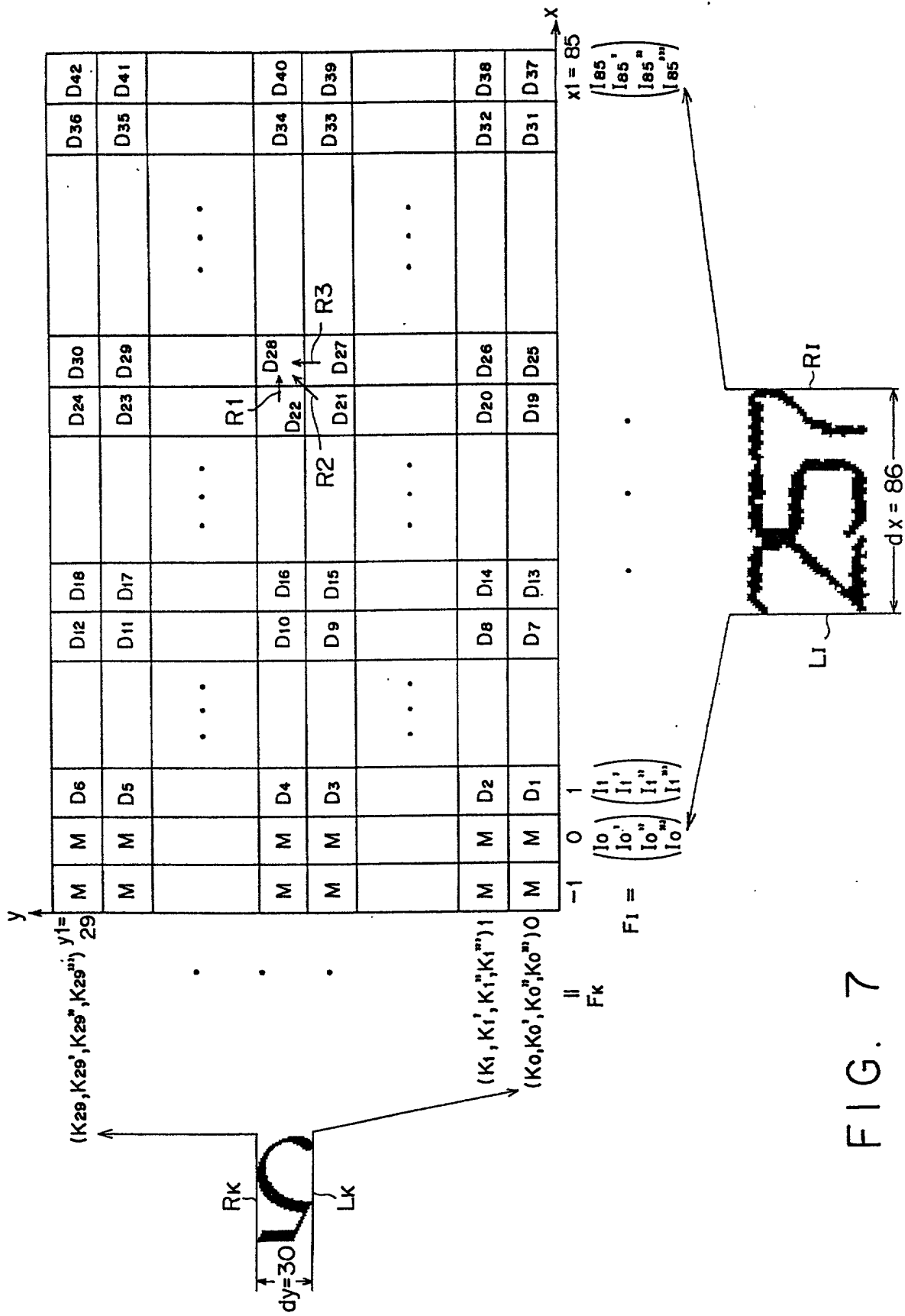
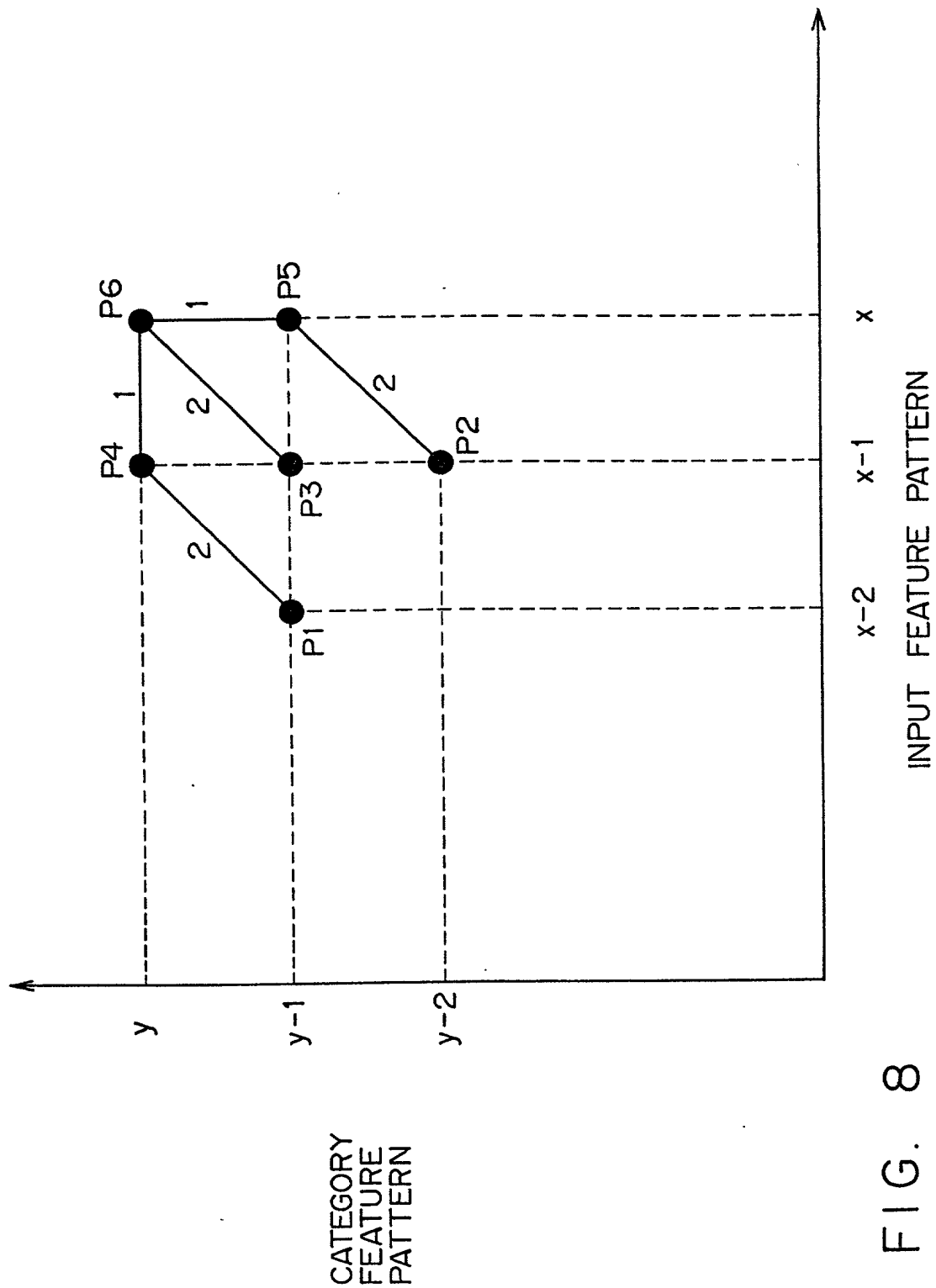


FIG. 7





START

INITIALIZATION  
 $q(-1, y) = q(0, y) = M$   
 $q(-1, y) = q(0, y) = 0$   
 $0 \leq y \leq y_1$

$x = 1$

$q(x, 0) = 2d(x, 0)$   
 $q(x, 0) = 2$

COMPUTING  $q(x, y)$  BY  
GRADUAL CHANGE EQUATION  
FOR  $1 \leq y \leq y_1$   
COMPUTING  $g(x, y)$  BASED  
ON COMPUTATION RESULT

$x = x + 1$

$x > x_1$

END

FIG. 9

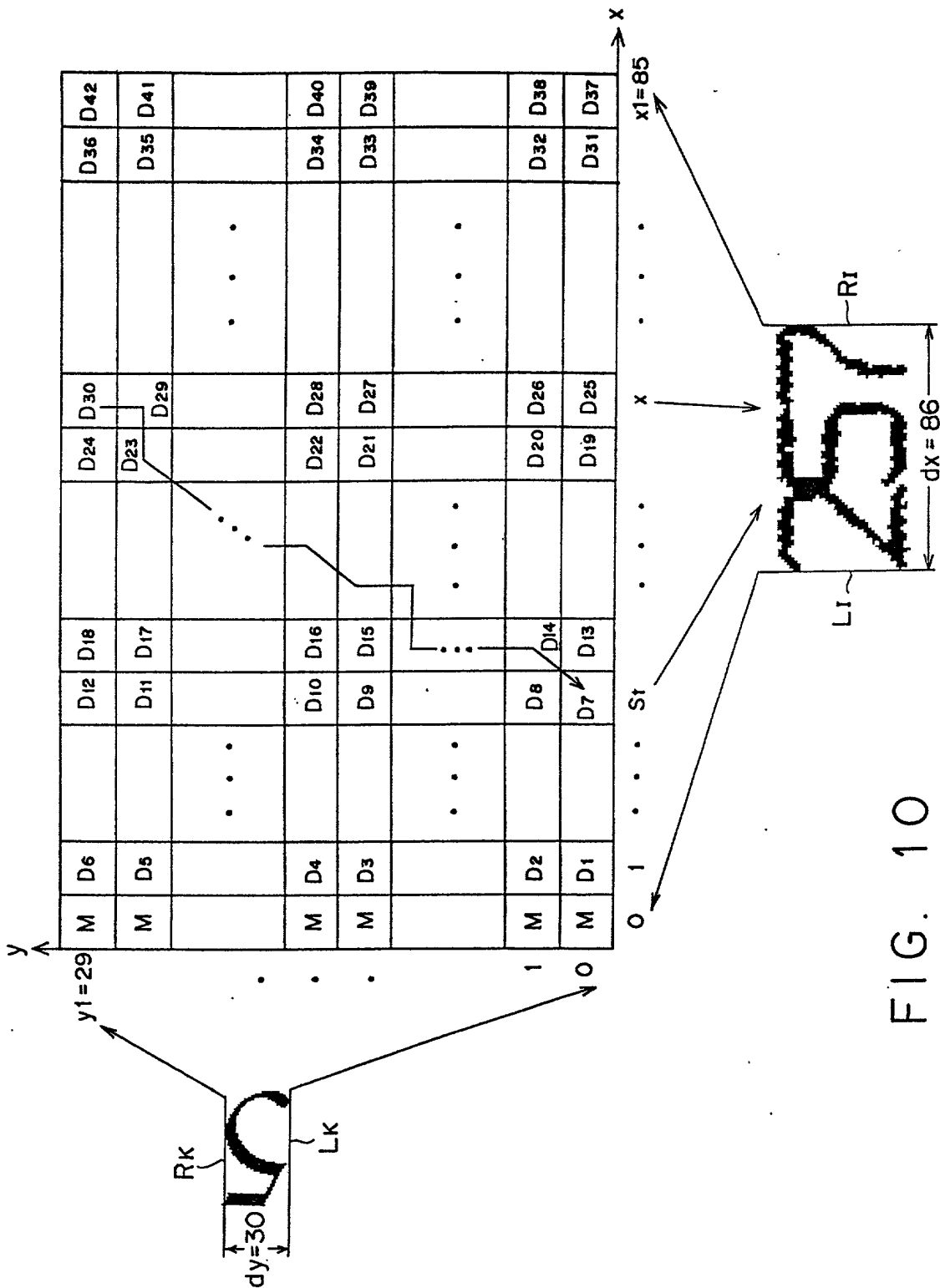


FIG. 10

[illegible]

...



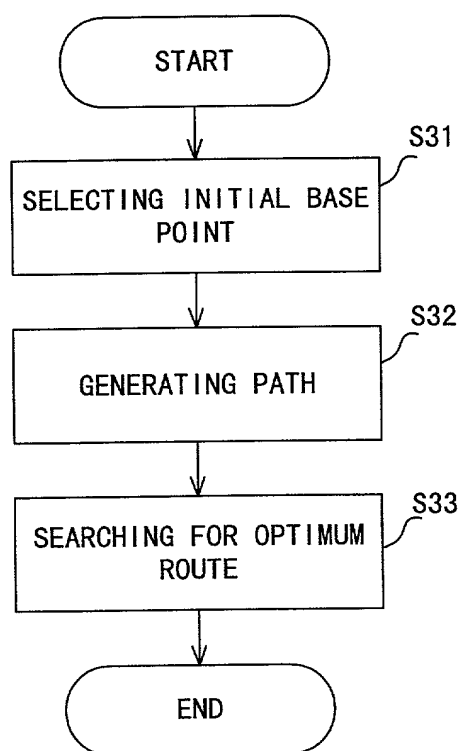


FIG. 13

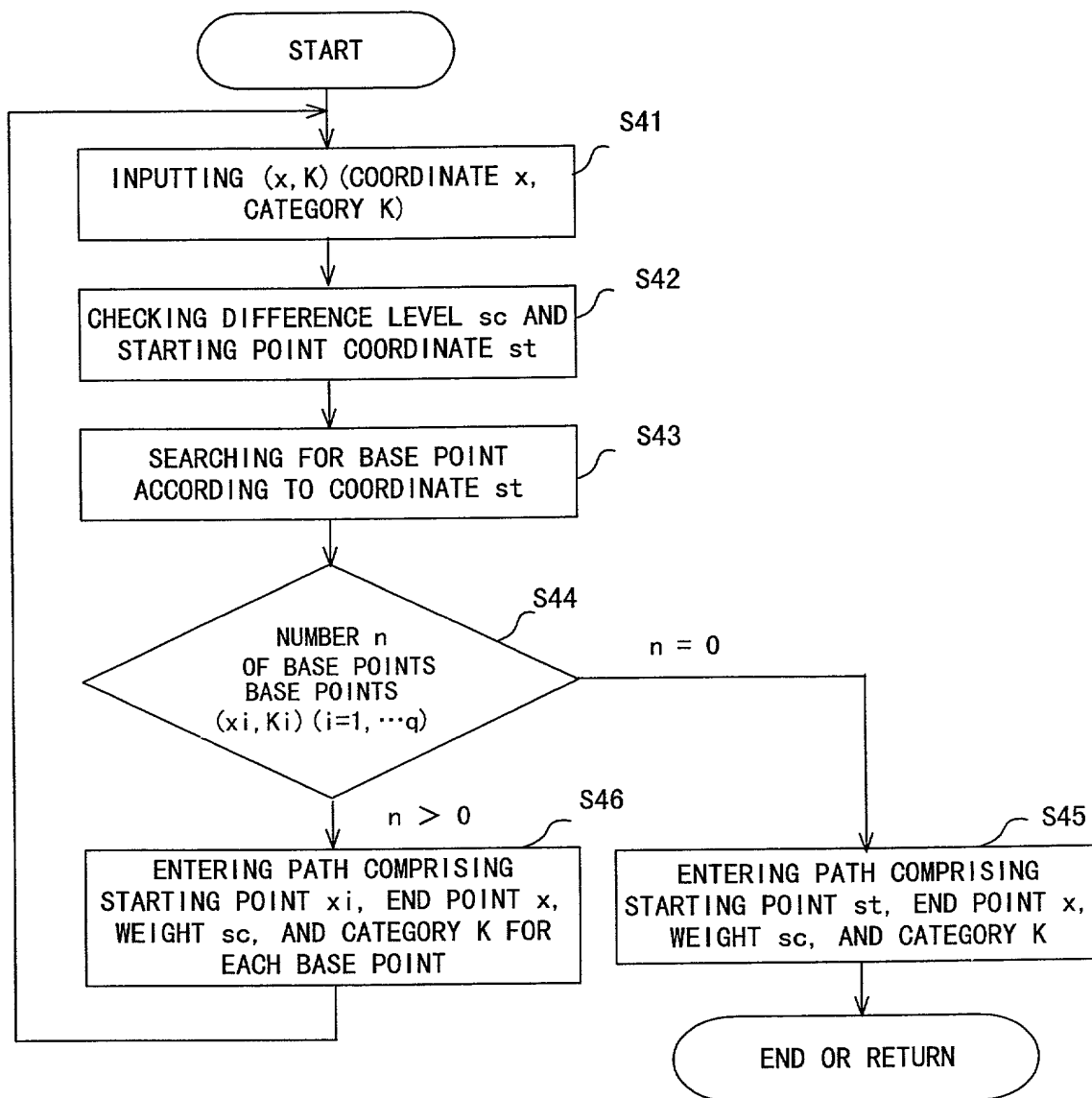


FIG. 14

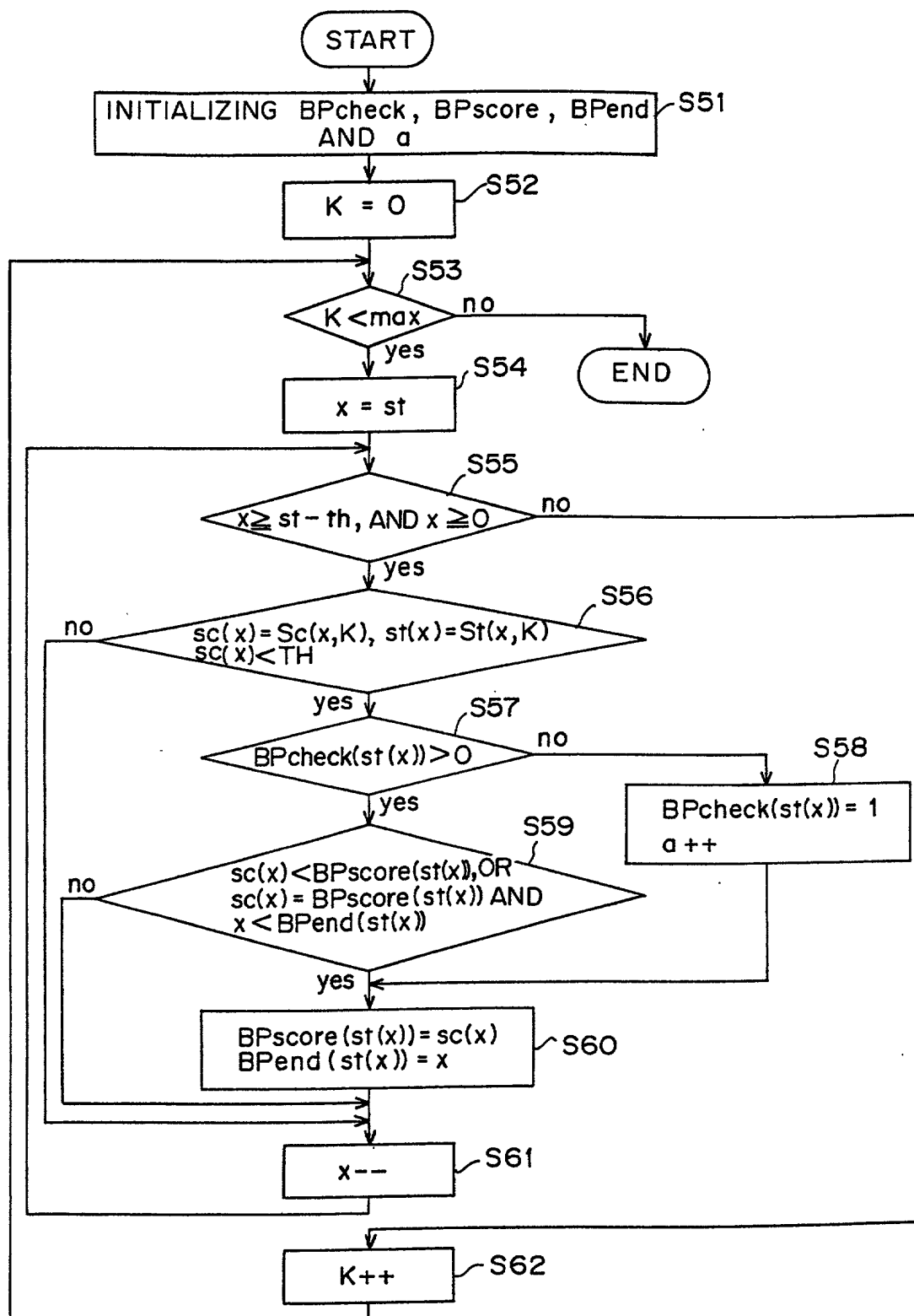


FIG. 15

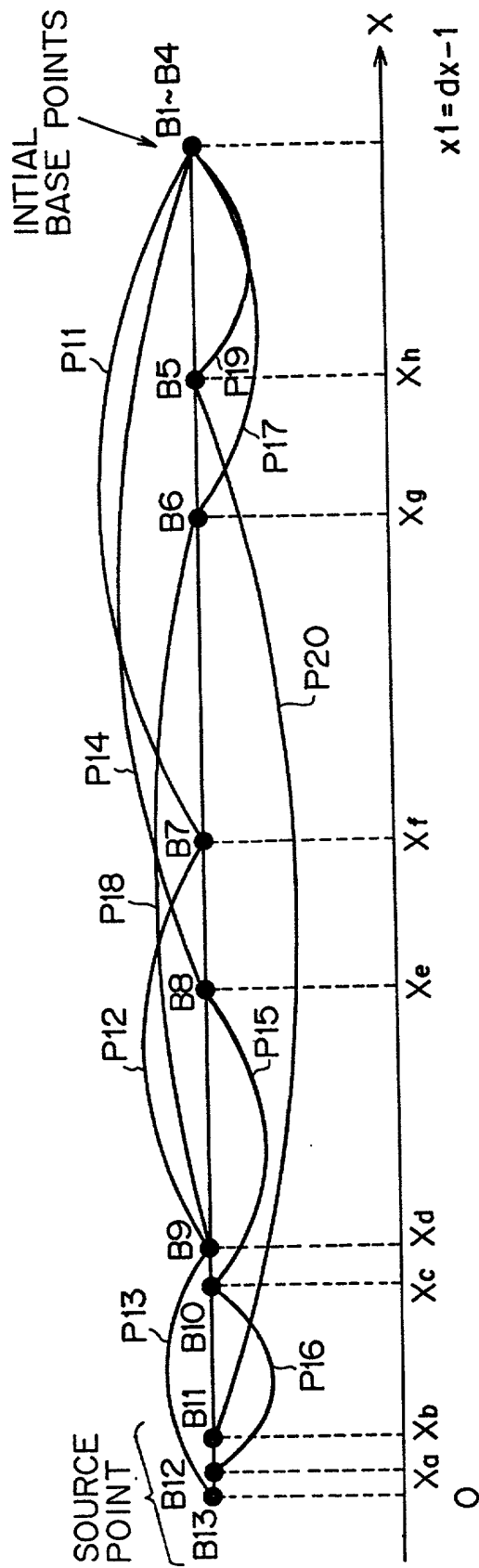


FIG. 16



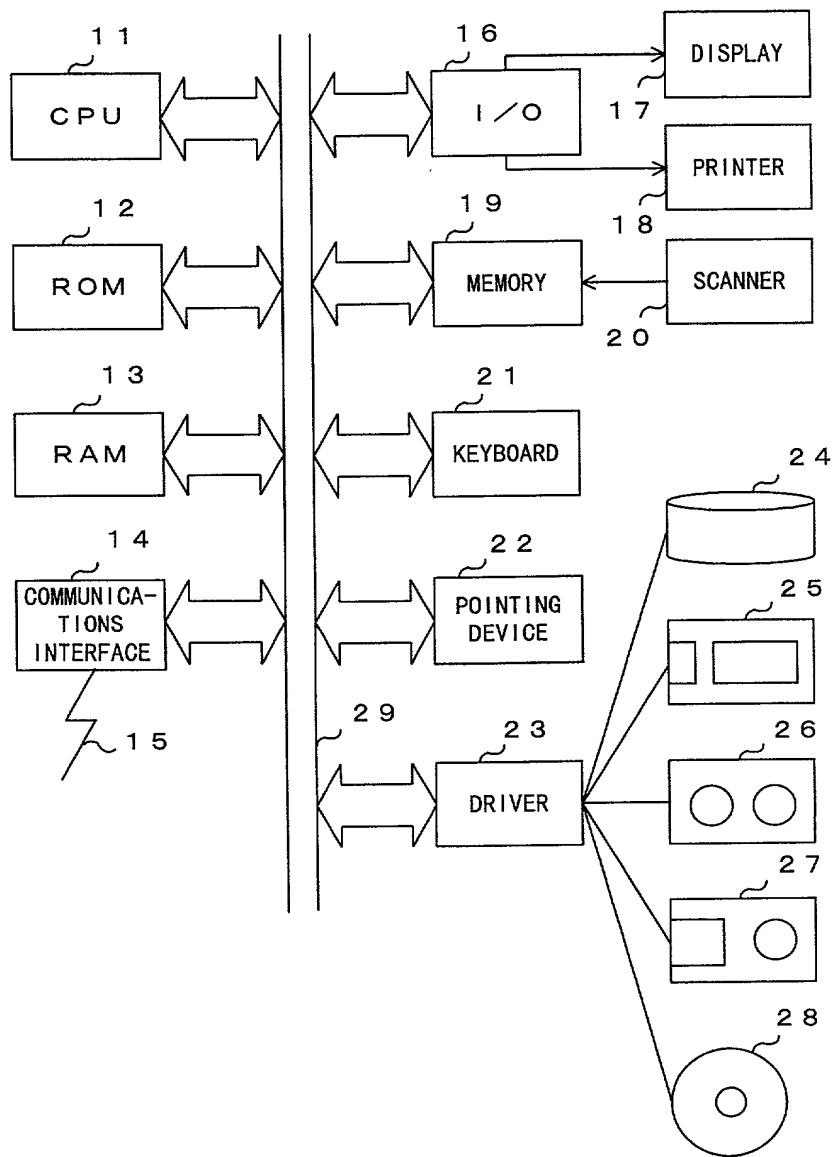


FIG. 17

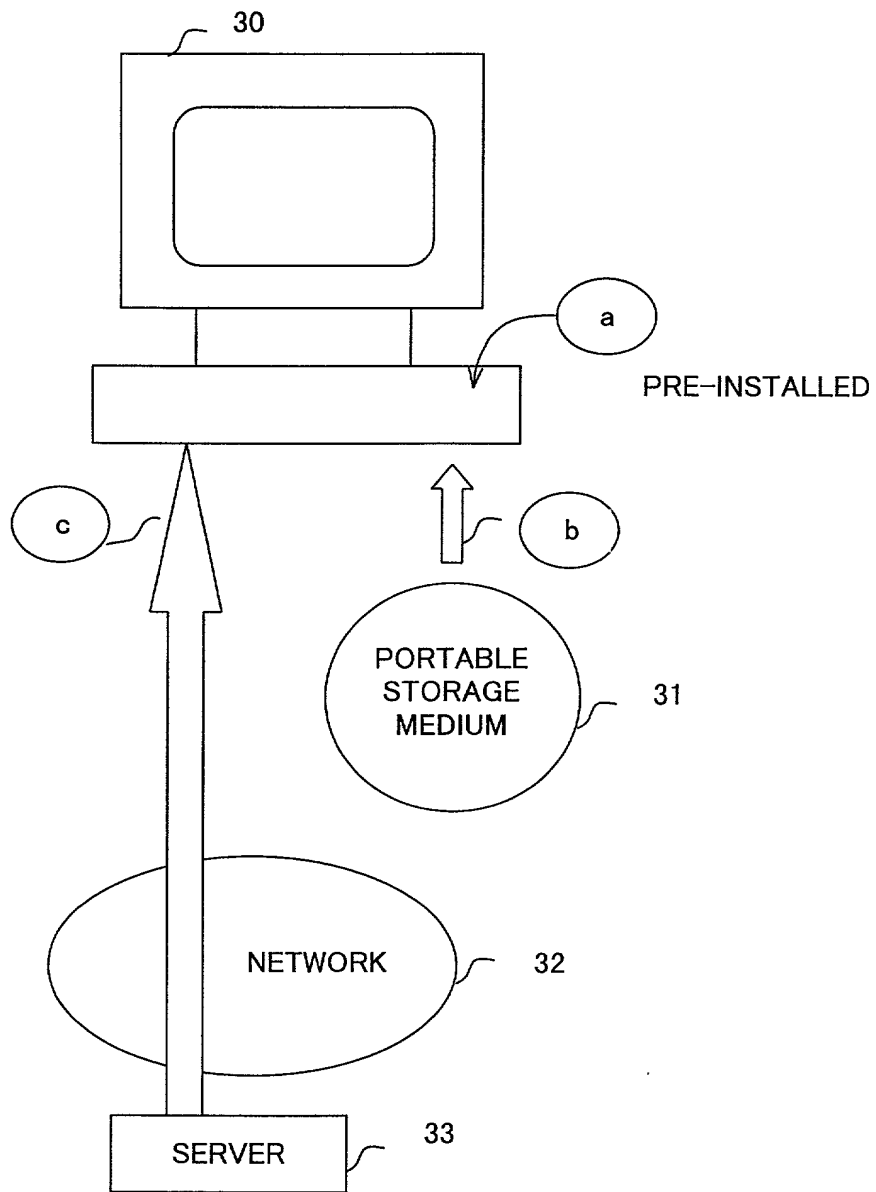


FIG. 18

Under the Paperwork Reduction Act of 1995, no persons are required to respond to a collection of information unless it displays a valid OMB control number.

## Declaration and Power of Attorney For Patent Application

### 特許出願宣言書及び委任状

### Japanese Language Declaration

### 日本語宣言書

下記の氏名の発明者として、私は以下の通り宣言します。

As a below named inventor, I hereby declare that:

私の住所、私書箱、国籍は下記の私の氏名の後に記載された通りです。

My residence, post office address and citizenship are as stated next to my name.

下記の名称の発明に関して請求範囲に記載され、特許出願している発明内容について、私が最初かつ唯一の発明者（下記の氏名が一つの場合）もしくは最初かつ共同発明者であると（下記の名称が複数の場合）信じています。

I believe I am the original, first and sole inventor (if only one name is listed below) or an original, first and joint inventor (if plural names are listed below) of the subject matter which is claimed and for which a patent is sought on the invention entitled

PATTERN SEGMENTATION APPARATUS AND

PATTERN RECOGNITION APPARATUS

上記発明の明細書（下記の欄でX印がついていない場合は、本書に添付）は、

the specification of which is attached hereto unless the following box is checked:

☐ 月 日に提出され、米国出願番号または特許協定条約  
国際出願番号を \_\_\_\_\_ とし、  
(該当する場合) \_\_\_\_\_ に訂正されました。

☐ was filed on \_\_\_\_\_  
as United States Application Number or  
PCT International Application Number  
\_\_\_\_\_ and was amended on  
\_\_\_\_\_ (if applicable).

私は、特許請求範囲を含む上記訂正後の明細書を検討し、  
内容を理解していることをここに表明します。

I hereby state that I have reviewed and understand the contents of  
the above identified specification, including the claims, as  
amended by any amendment referred to above.

私は、連邦規則法典第37編第1条56項に定義されると  
おり、特許資格の有無について重要な情報を開示する義務が  
あることを認めます。

I acknowledge the duty to disclose information which is material to  
patentability as defined in Title 37, Code of Federal Regulations,  
Section 1.56.

Page 1 of 2

Burden Hour Statement: This form is estimated to take 0.4 hours to complete. Time will vary depending upon the needs of the individual case. Any comments on the amount of time you are required to complete this form should be sent to the Chief Information Officer, Patent and Trademark Office, Washington, DC 20231. DO NOT SEND FEES OR COMPLETED FORMS TO THIS ADDRESS. SEND TO: Commissioner of Patents and Trademarks, Washington, DC 20231.

Under the Paperwork Reduction Act of 1995, no persons are required to respond to a collection of information unless it displays a valid OMB control number.

### Japanese Language Declaration (日本語宣言書)

私は、米国法典第35編119条(a)-(d)項又は365条(b)項に基き下記の、米国外の国の少なくとも一ヶ国を指定している特許協力条約365(a)項に基き国際出願、又は外国での特許出願もしくは発明者証の出願についての外国優先権をここに主張するとともに、優先権を主張している、本出願の前に出願された特許または発明者証の外国出願を以下に、枠内をマークすることで、示しています。

#### Prior Foreign Application(s)

外国での先行出願

11-191576

(Number)

(番号)

Japan

(Country)

(国名)

I hereby claim foreign priority under Title 35, United States Code, Section 119 (a)-(d) or 365(b) of any foreign application(s) for patent or inventor's certificate, or 365(a) of any PCT International application which designated at least one country other than the United States, listed below and have also identified below, by checking the box, any foreign application for patent or inventor's certificate, or PCT International application having a filing date before that of the application on which priority is claimed.

Priority Not Claimed

優先権主張なし

6th/July/1999

(Day/Month/Year Filed)

(出願年月日)

☐

(Number)

(番号)

(Country)

(国名)

(Day/Month/Year Filed)

(出願年月日)

☐

私は、第35編米国法典119条(e)項に基いて下記の米特許出願規定に記載された権利をここに主張いたします。

(Application No.)

(出願番号)

(Filing Date)

(出願日)

(Application No.)

(出願番号)

(Filing Date)

(出願日)

私は、下記の米国法典第35編120条に基いて下記の米特許出願に記載された権利、又は米国を指定している特許協力条約365条(c)に基き権利をここに主張します。また、本出願の各請求範囲の内容が米国法典第35編112条第1項又は特許協力条約で規定された方法で先行する米特許出願に開示されていない限り、その先行米特許出願提出日以降で本出願の日本国内または特許協力条約国際提出日までの期間中に入子された、連邦規則法典第37編1条56項で定義された特許資格の有無に関する重要な情報について開示義務があることを認識しています。

I hereby claim the benefit under Title 35, United States Code, Section 120 of any United States application(s), or 365(c) of any PCT International application designating the United States, listed below and, insofar as the subject matter of each of the claims of this application is not disclosed in the prior United States or PCT International application in the manner provided by the first paragraph of Title 35, United States Code Section 112, I acknowledge the duty to disclose information which is material to patentability as defined in Title 37, Code of Federal Regulations, Section 1.56 which became available between the filing date of the prior application and the national or PCT International filing date of application.

(Application No.)

(出願番号)

(Filing Date)

(出願日)

(Status: Patented, Pending, Abandoned)

(現況: 特許許可済、係属中、放棄済)

(Application No.)

(出願番号)

(Filing Date)

(出願日)

(Status: Patented, Pending, Abandoned)

(現況: 特許許可済、係属中、放棄済)

私は、私自身の知識に基づいて本宣言書中で私が行なう表明が真実であり、かつ私の入手した情報と私の信じていることに基き表明が全て真実であると信じていること、さらに故意になされた虚偽の表明及びそれと同等の行為は米国法典第18編第1001条に基き、罰金または拘禁、もしくはその両方により処罰されること、そしてそのような故意による虚偽の表明を行なえば、出願した、又は既に許可された特許の有効性が失われることを認識し、よってここに上記のごとく宣誓を致します。

I hereby declare that all statements made herein of my own knowledge are true and that all statements made on information and belief are believed to be true; and further that these statements were made with the knowledge that willful false statements and the like so made are punishable by fine or imprisonment, or both, under Section 1001 of Title 18 of the United States Code and that such willful false statements may jeopardize the validity of the application or any patent issued thereon.

Under the Paperwork Reduction Act of 1995, no persons are required to respond to a collection of information unless it displays a valid OMB control number.

### Japanese Language Declaration (日本語宣言書)

委任状: 私は下記の発明者として、本出願に関する一切の  
手続を米特許商標局に対して遂行する弁護士または代理人  
として、下記の者を指名いたします。(弁護士、または代理  
人の氏名及び登録番号を明記のこと)

James D. Halsey, Jr., 22,729; Harry John Staas, 22,010; David M. Pitcher, 25,908; John C. Garvey, 28,607; J. Randall Beckers,  
30,358; William F. Herbert, 31,024; Richard A. Golhofer, 31,106; Mark J. Henry, 36,162; Gene M. Garner II, 34,172; Michael D.  
Stein, 37,240; Paul I. Kravetz, 35,230; Gerald P. Joyce, III, 37,648; Todd E. Marlette, 35,269; Harlan B. Williams, Jr., 34,756;  
George N. Stevens, 36,938; Michael C. Soldner, 41,455; Norman L. Ourada, 41,235; Kevin R. Spivak, P-43,148; and William M.  
Schantler, 35,348 (agent)

書類送付先

POWER OF ATTORNEY: As a named inventor, I hereby appoint  
the following attorney(ies) and/or agent(s) to prosecute this  
application and transact all business in the Patent and Trademark  
Office connected therewith (list name and registration number)

Send Correspondence to:

STAAS & HALSEY  
700 Eleventh Street, N.W.  
Suite 500  
Washington, D.C. 20001

直接電話連絡先: (名前及び電話番号)

Direct Telephone Calls to: (name and telephone number)

STAAS & HALSEY  
(202) 434-1500

唯一または第一発明者名	Full name of sole or first inventor
	Hiroaki TAKEBE
発明者の署名	Inventor's signature
日付	Date
	<i>Hiroaki Takebe</i> May 8, 2000
住所	Residence
	Kanagawa, Japan
国籍	Citizenship
	Japan
私書箱	Post Office Address
	c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan
第二共同発明者	Full name of second joint inventor, if any
	Yoshinobu HOTTA
第二共同発明者	Second inventor's signature
日付	Date
	<i>Yoshinobu Hotta</i> May 8, 2000
住所	Residence
	Kanagawa, Japan
国籍	Citizenship
	Japan
私書箱	Post Office Address
	c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan

(第三以降の共同発明者についても同様に記載し、署名をす  
ること)

(Supply similar information and signature for third and subsequent  
joint inventors.)

第三共同発明者		Full name of third joint inventor, if any Satoshi NAOI	
第三共同発明者	日付	Third inventor's signature <i>Satoshi Naoi</i>	Date May 8, 2000
住 所		Residence Kanagawa, Japan	
国 籍		Citizenship Japan	
私書箱		Post Office Address c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan	
第四共同発明者		Full name of fourth joint inventor, if any	
第四共同発明者	日付	Fourth inventor's signature	Date
住 所		Residence	
国 籍		Citizenship	
私書箱		Post Office Address	

第五共同発明者		Full name of fifth joint inventor, if any	
第五共同発明者	日付	Fifth inventor's signature	Date
住 所		Residence	
国 籍		Citizenship	
私書箱		Post Office Address	
第六共同発明者		Full name of sixth joint inventor, if any	
第六共同発明者	日付	Sixth inventor's signature	Date
住 所		Residence	
国 籍		Citizenship	
私書箱		Post Office Address	

(第七以降の共同発明者についても同様に  
記載し、署名をすること)

(Supply similar information and signature for  
seventh and subsequent joint inventors.)